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(54) **CONTROLLING A WORK MACHINE BASED ON IN-RUBBER TIRE/TRACK SENSOR**

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(71) Applicant: **Deere & Company**, Moline, IL (US)

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(72) Inventors: **Mark J. Cherney**, Potosi, WI (US);
Michael G. Kean, Maquoketa, IA (US)

(58) **Field of Classification Search**

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(73) Assignee: **Deere & Company**, Moline, IL (US)

See application file for complete search history.

(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 127 days.

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This patent is subject to a terminal disclaimer.

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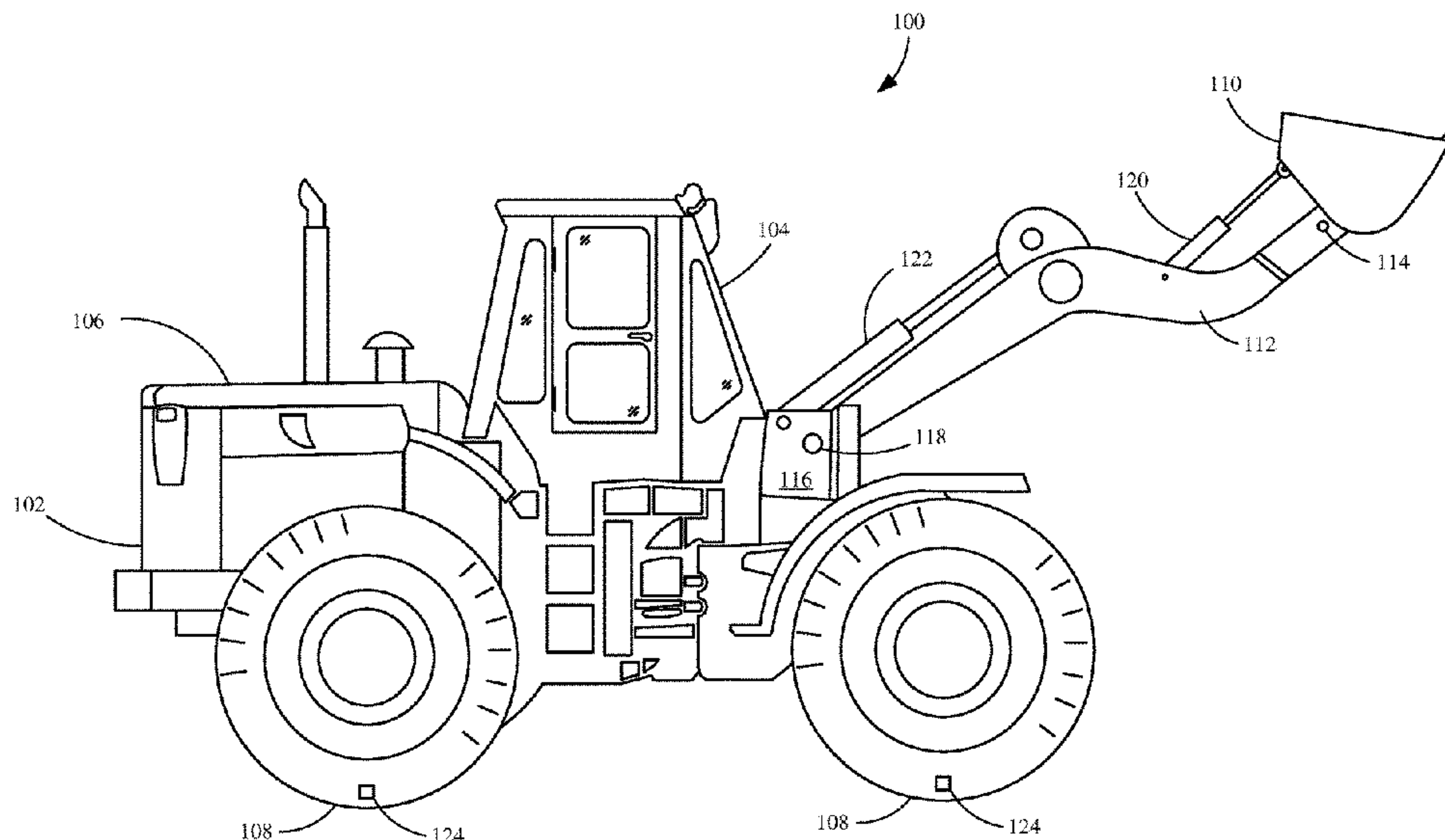
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(57) **ABSTRACT**

A stability control system identifies an actionable condition, such as instability, in an off-road mobile machine, based upon an in-rubber tire sensor. A remedial action is identified, and a control signal is generated to control the mobile machine to take the remedial action.

19 Claims, 12 Drawing Sheets



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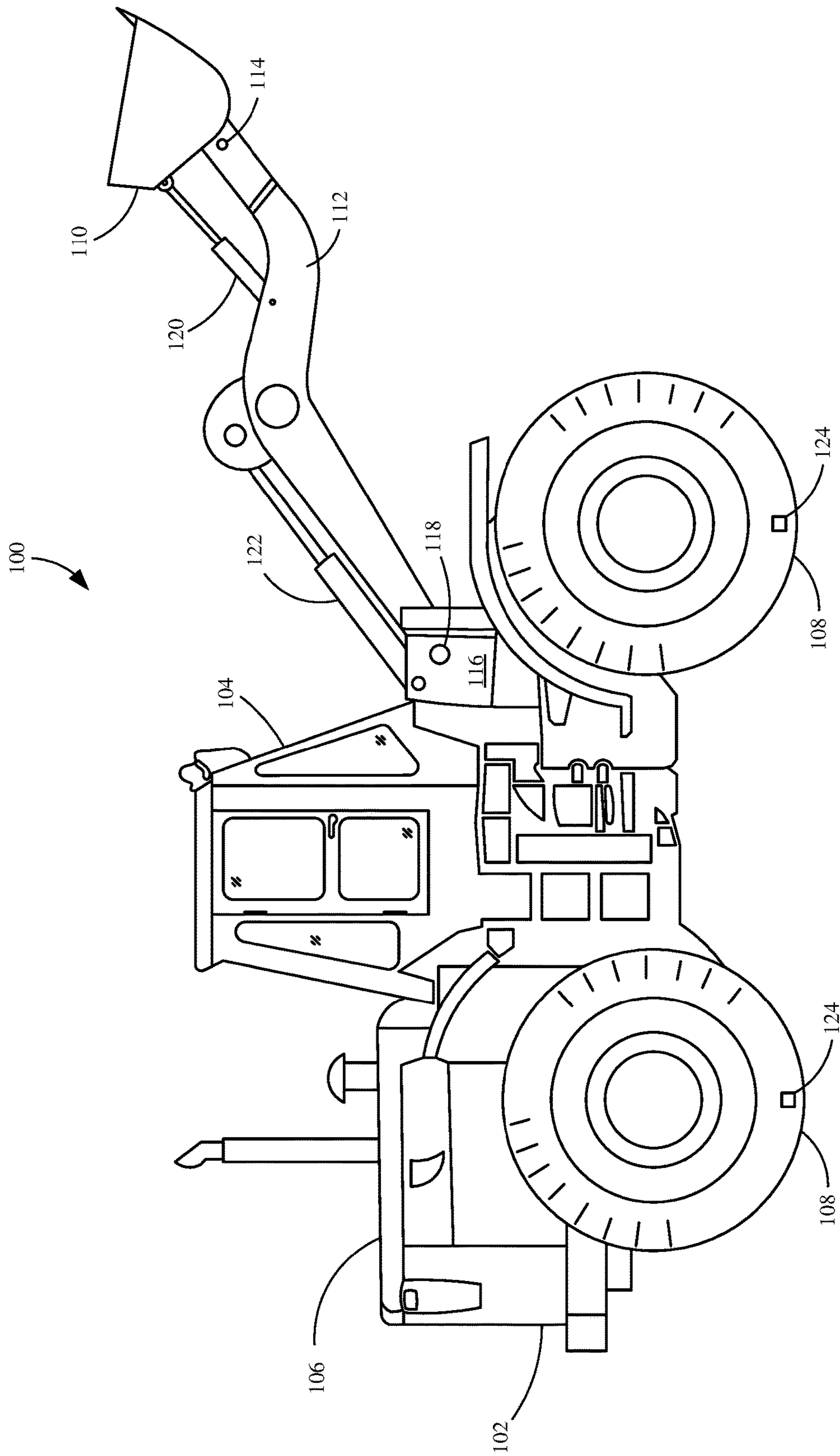


FIG. 1

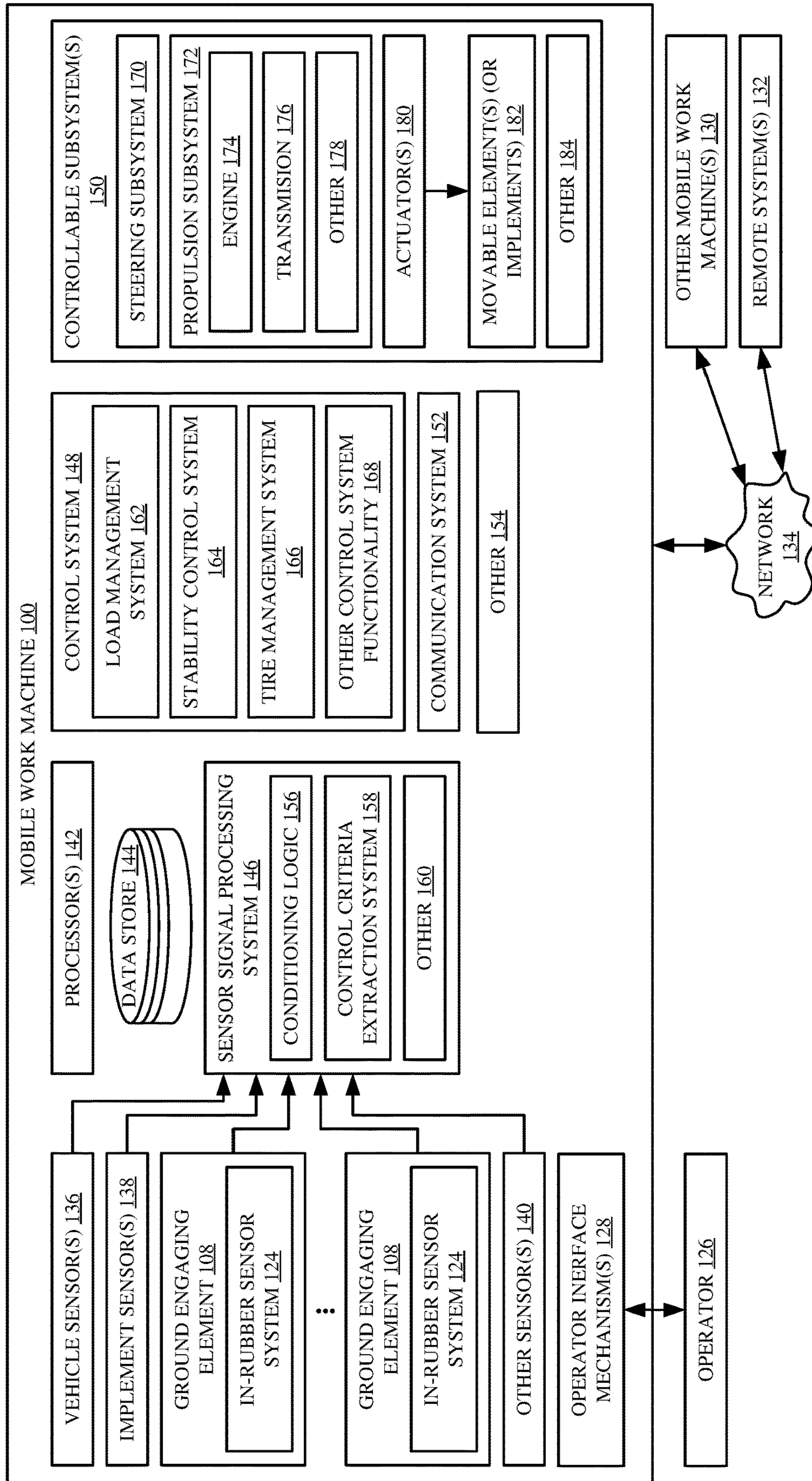


FIG. 2

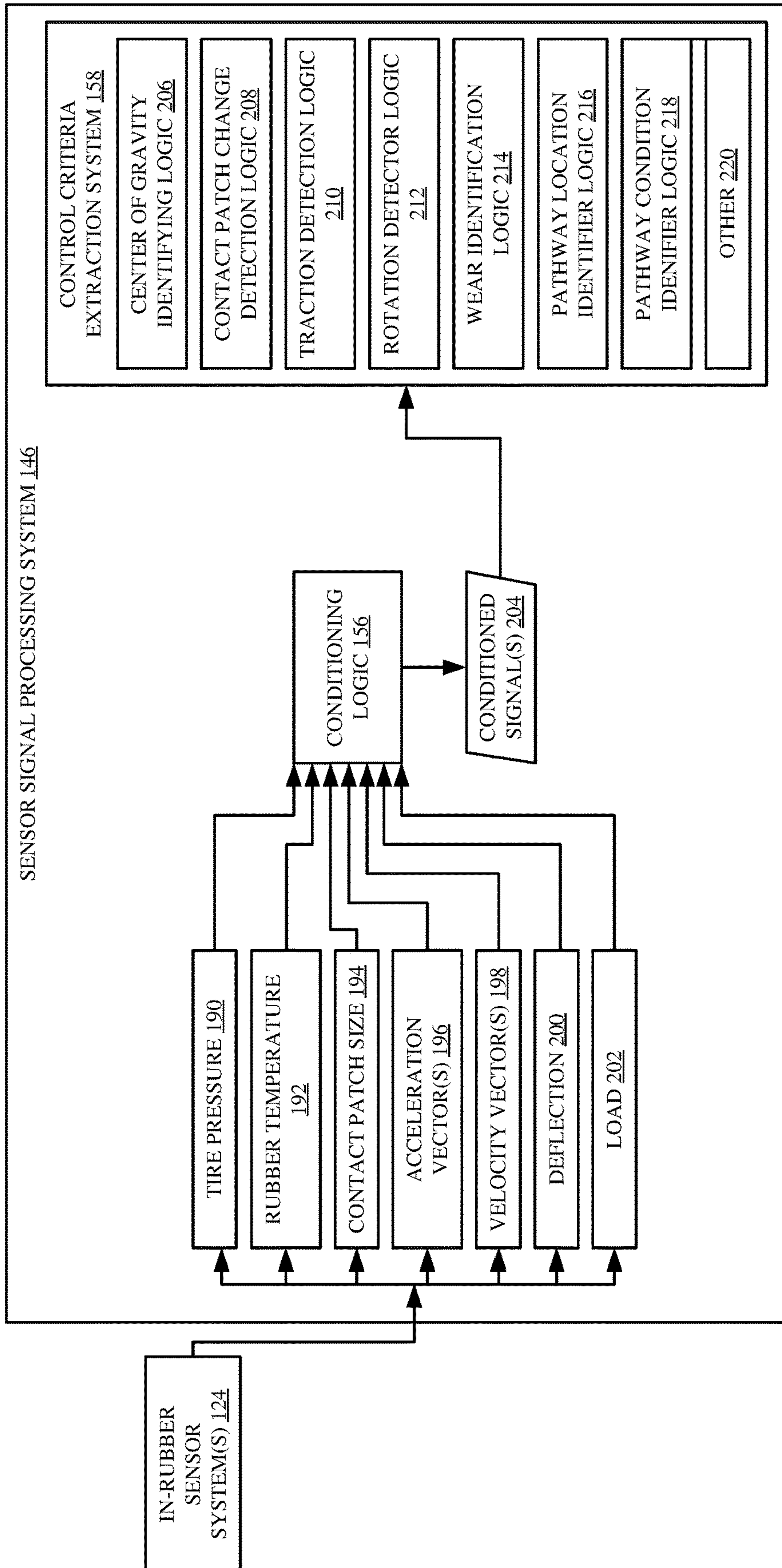


FIG. 3

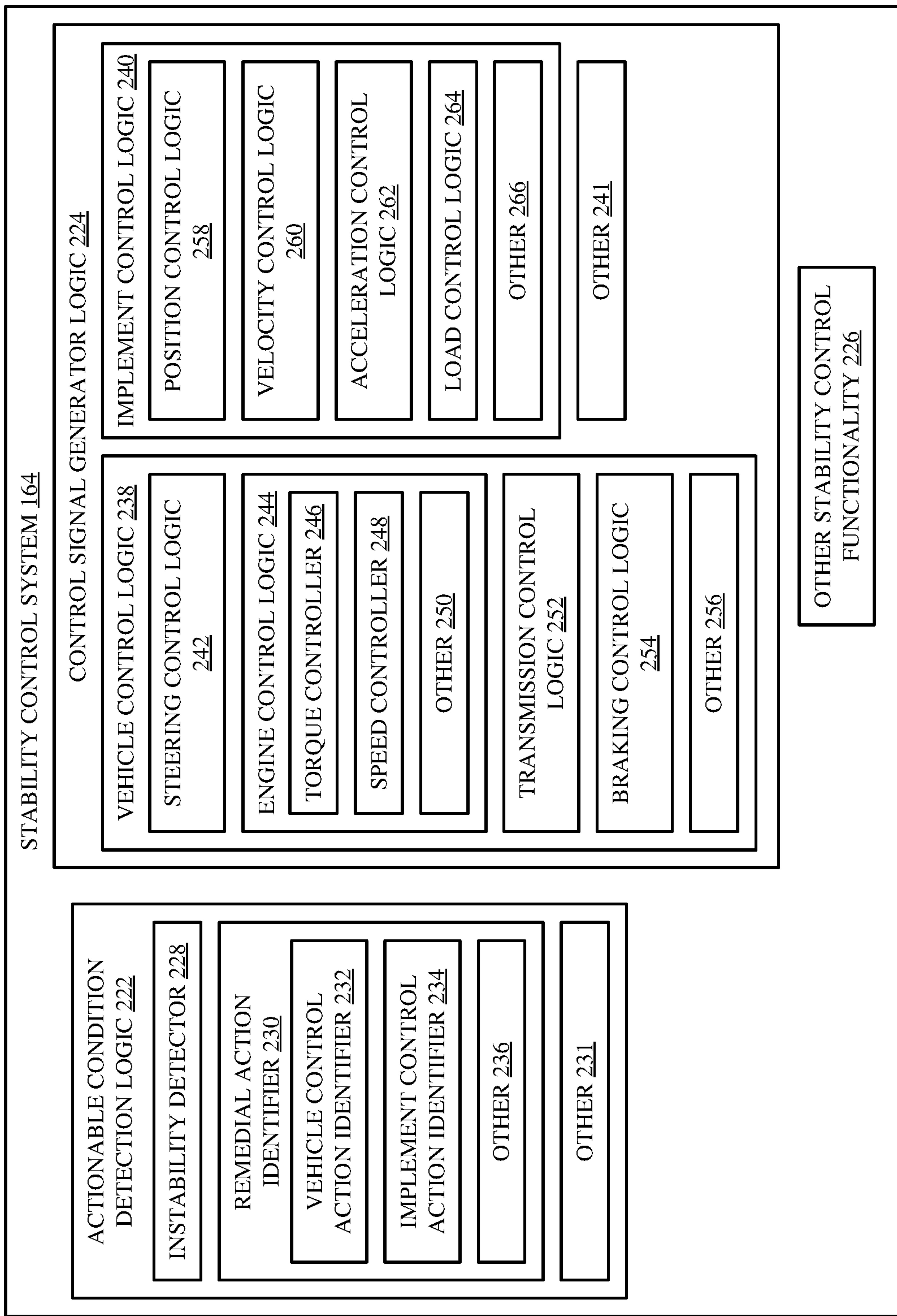


FIG. 4

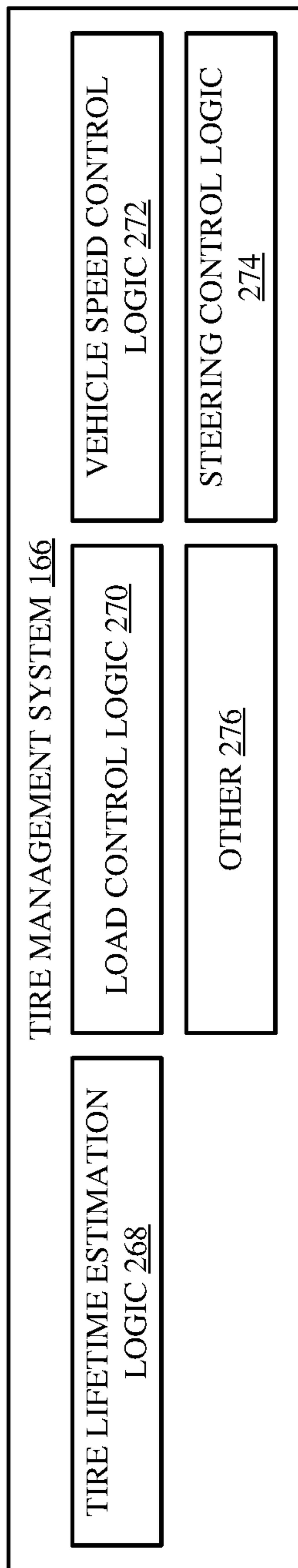


FIG. 5

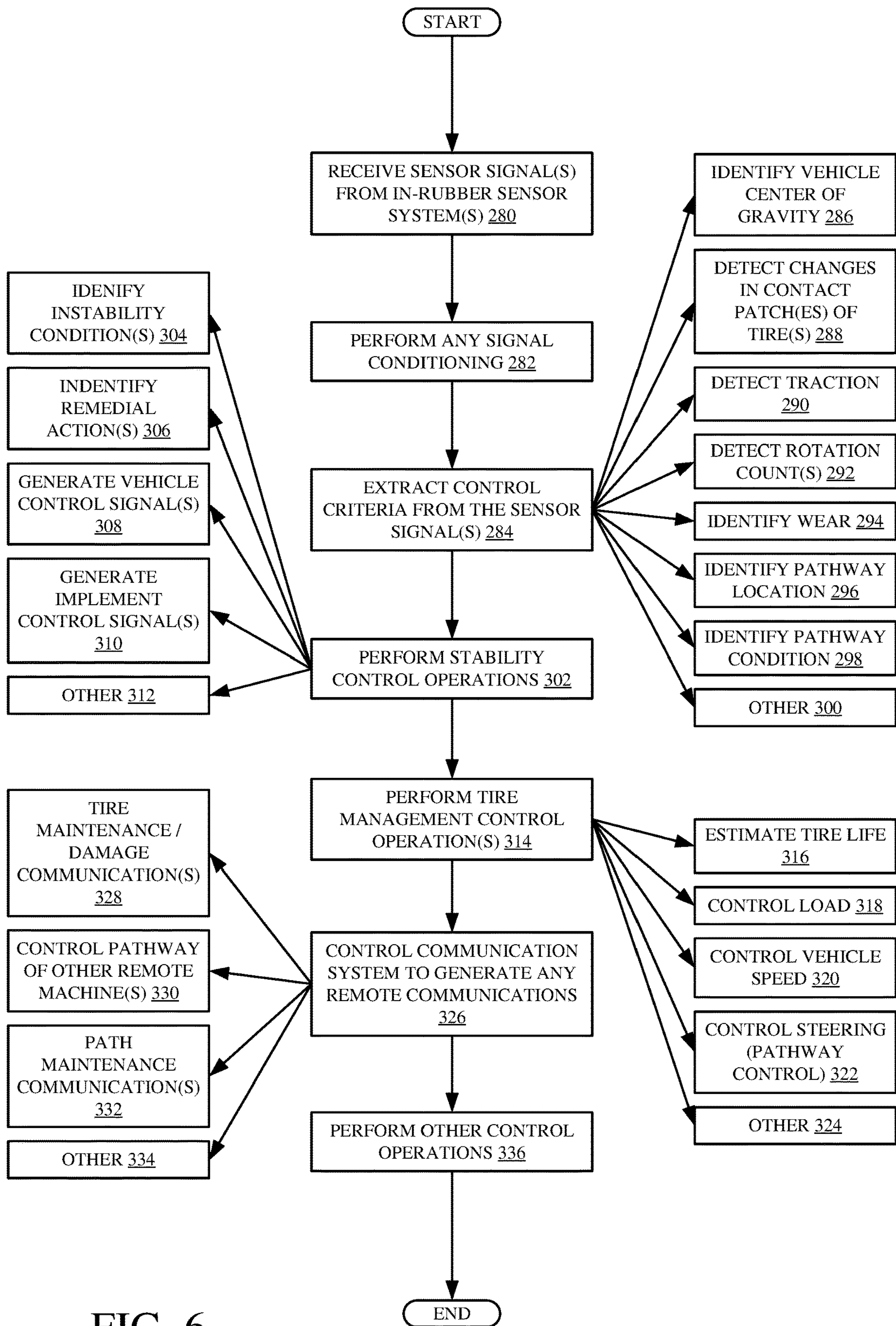


FIG. 6

FIG. 7

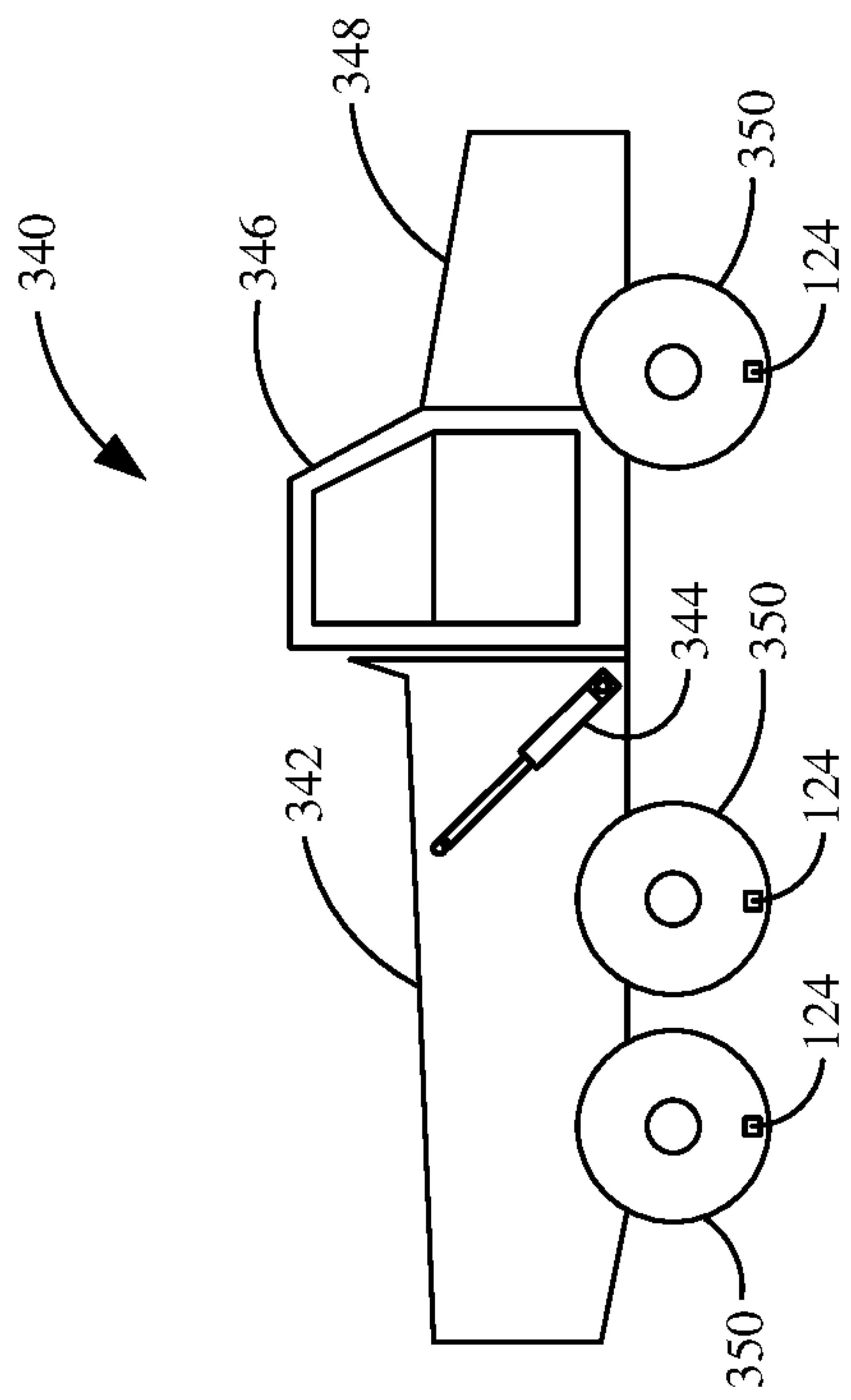
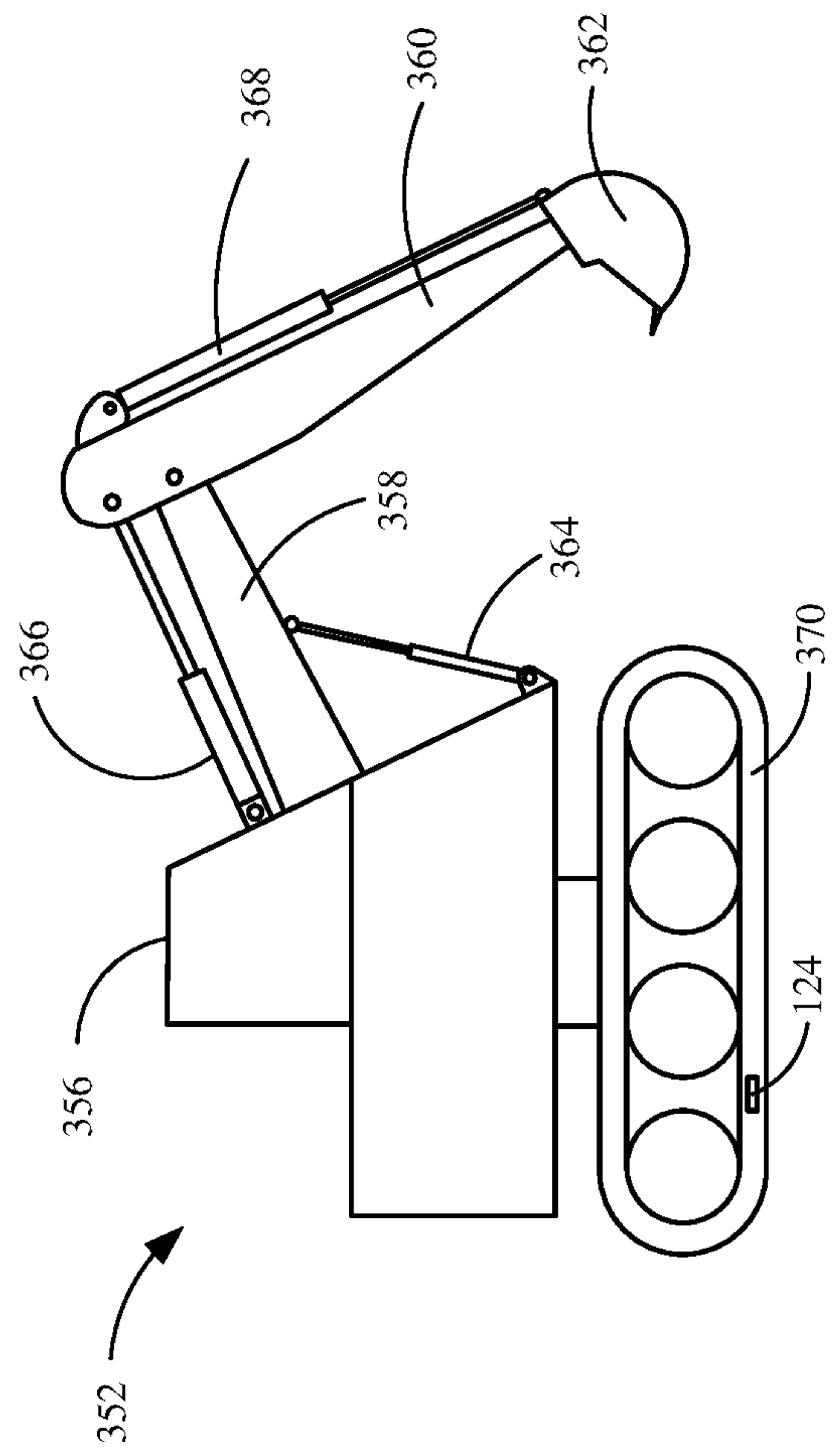


FIG. 8



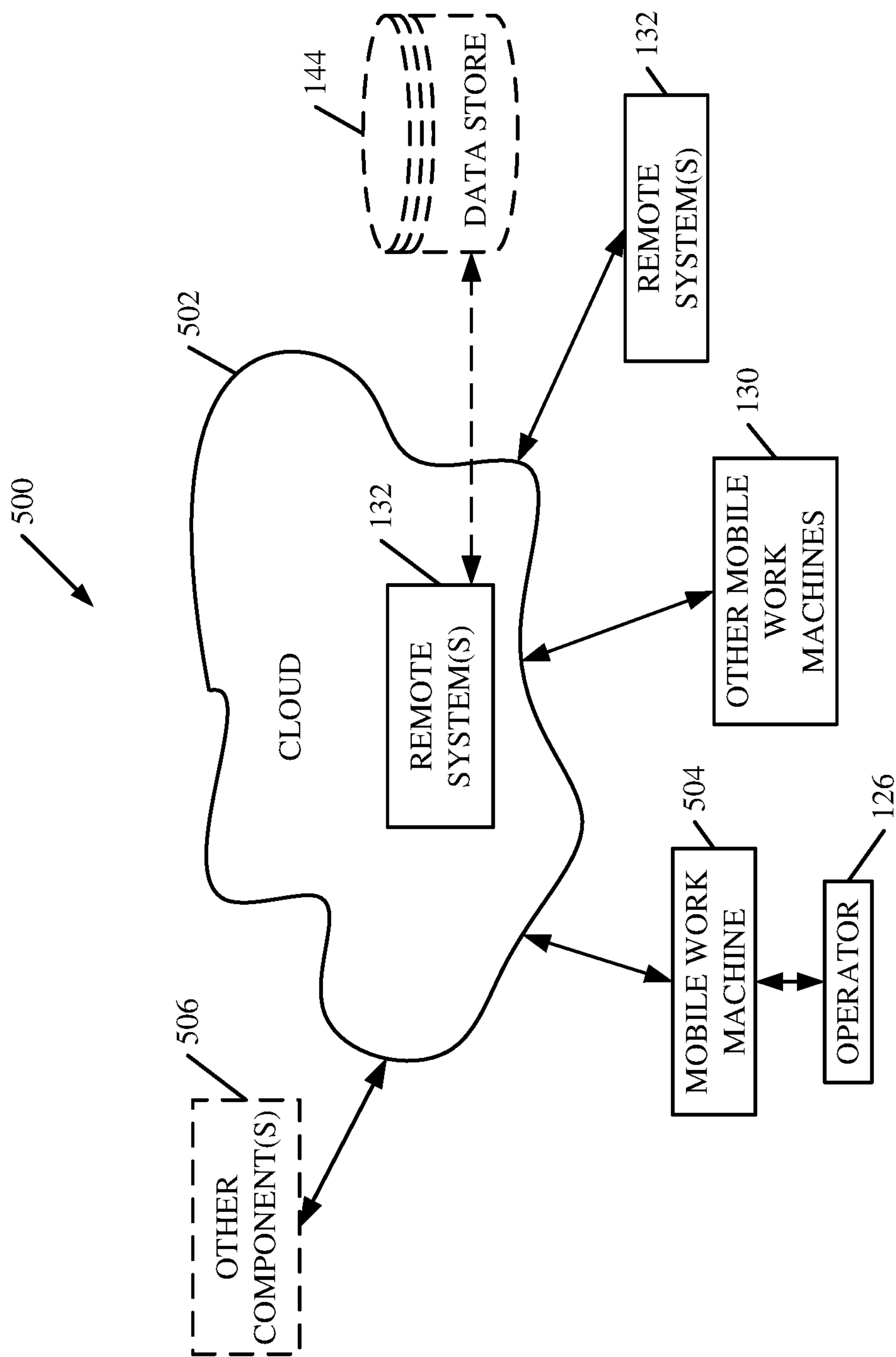


FIG. 9

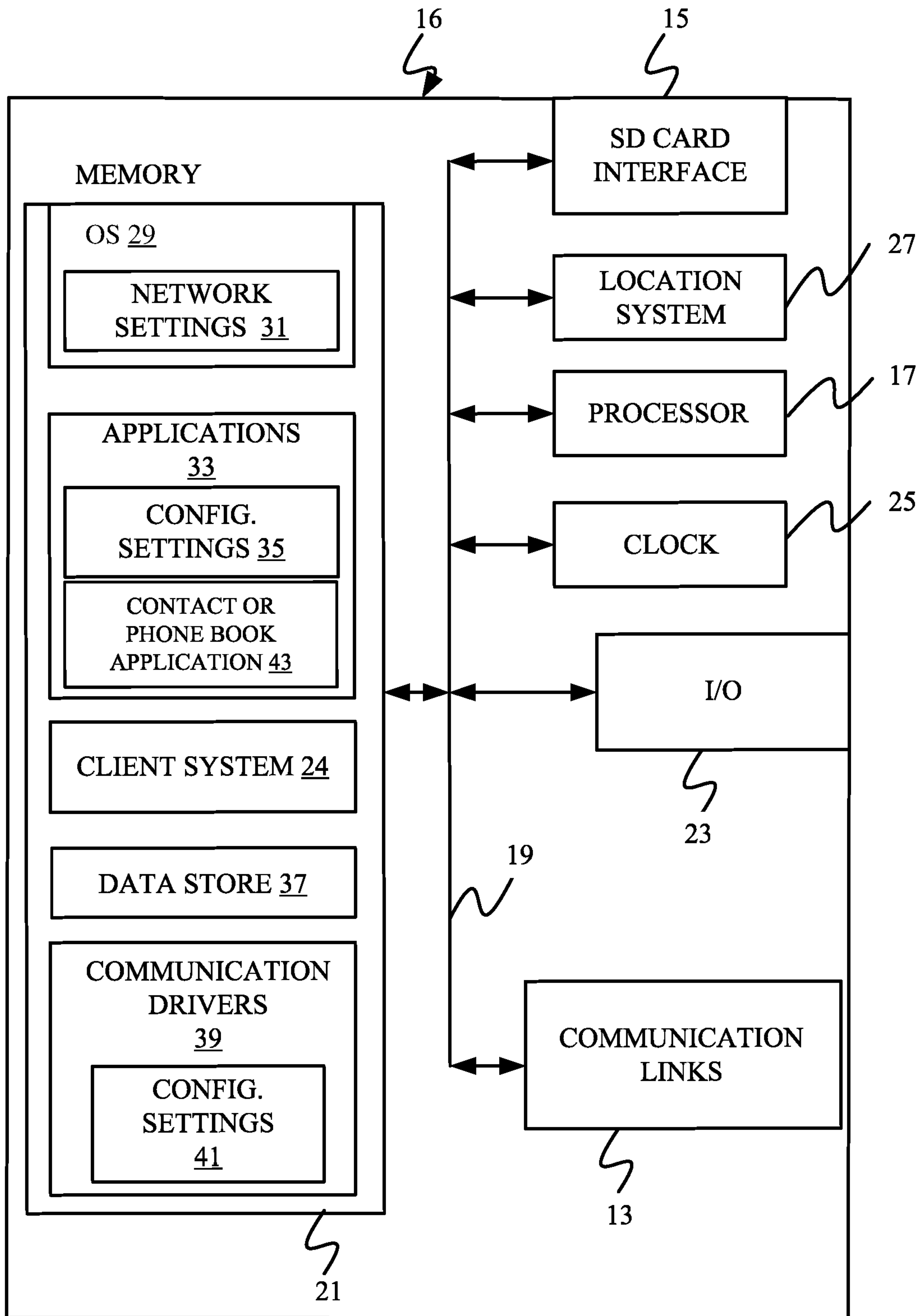


FIG. 10

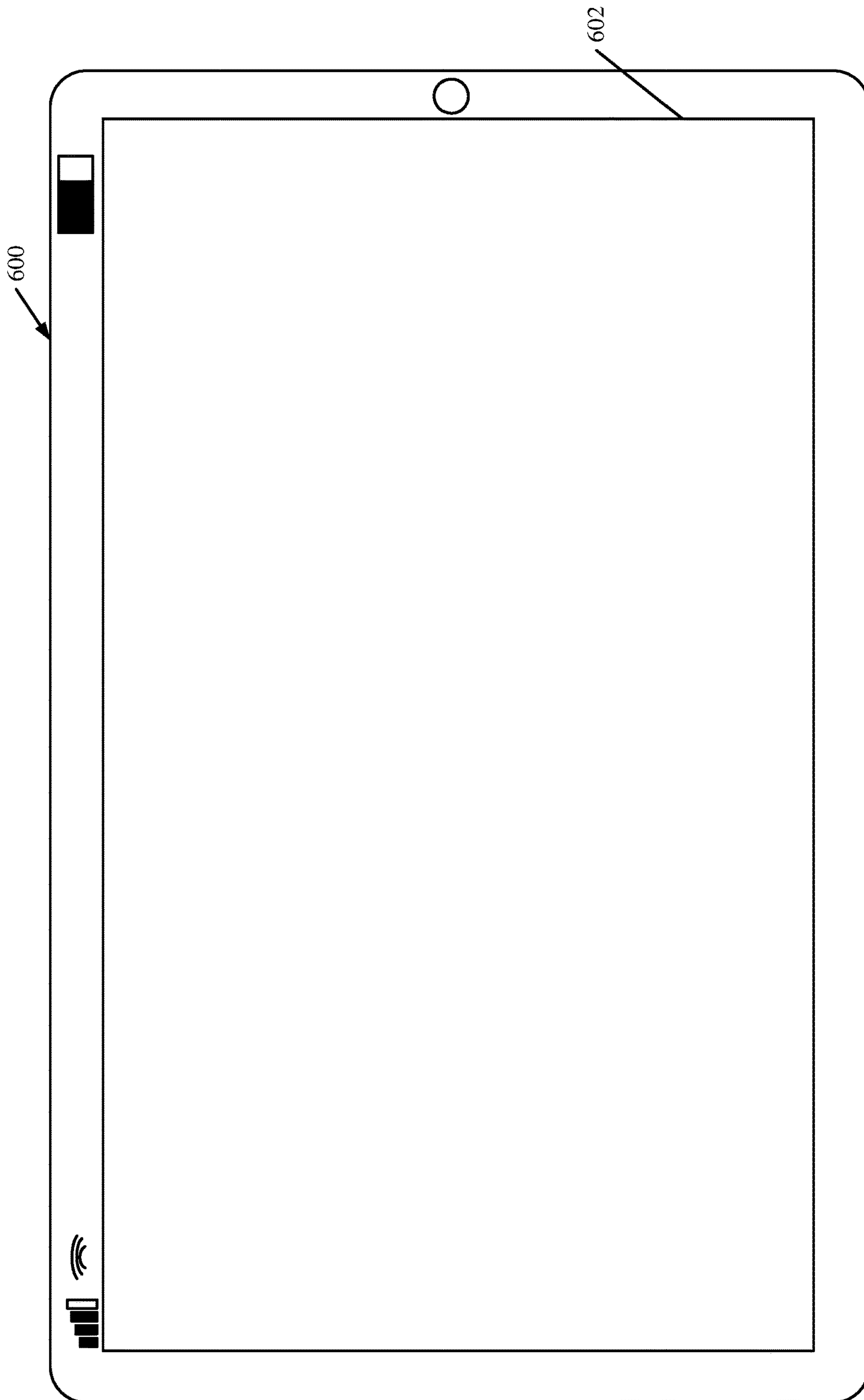


FIG. 11

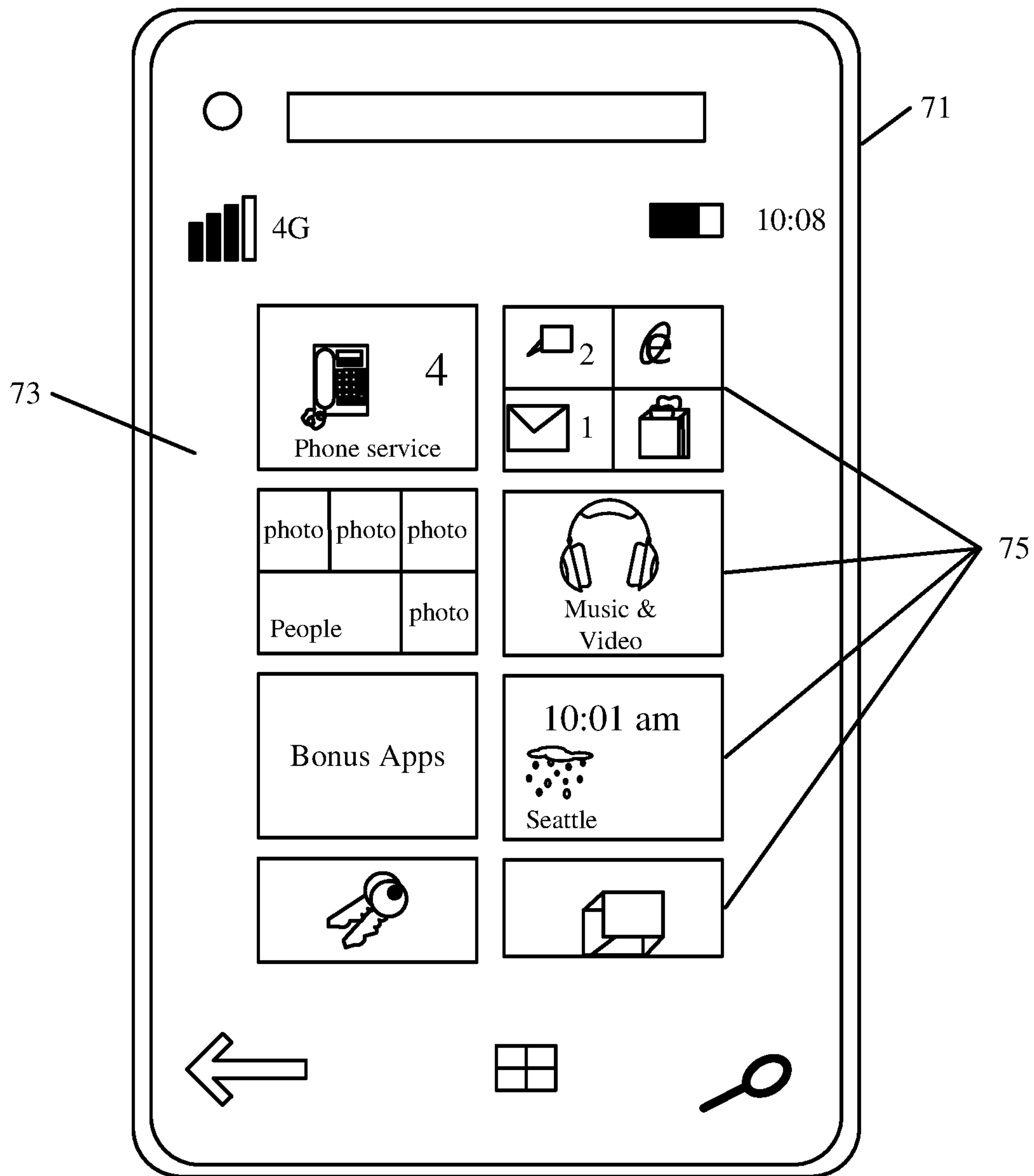


FIG. 12

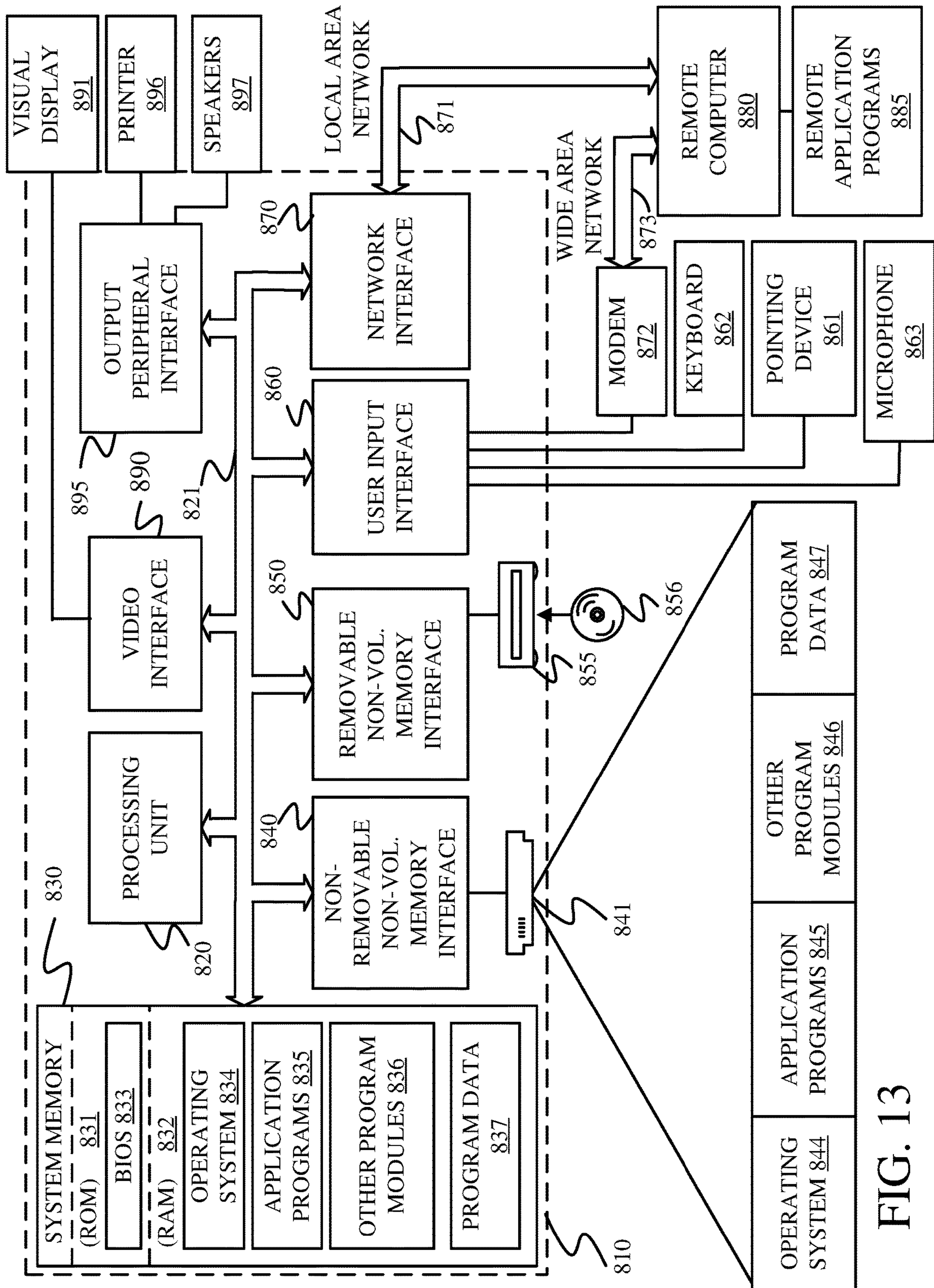


FIG. 13

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CONTROLLING A WORK MACHINE BASED ON IN-RUBBER TIRE/TRACK SENSOR

CROSS-REFERENCE TO RELATED APPLICATION

The present application is a continuation of and claims priority of U.S. patent application Ser. No. 16/122,275, filed Sep. 5, 2018, the content of which is hereby incorporated by reference in its entirety.

FIELD OF THE DESCRIPTION

The present description relates to using in-rubber sensors in the ground-engaging elements (e.g., tires or tracks) of an off-road vehicle, such as an agricultural vehicle, a forestry vehicle or construction vehicle. More specifically, the present description relates to controlling the vehicle based upon sensor signals from sensors.

BACKGROUND

There are a wide variety of different types of vehicles or mobile machines. Such machines include, for instance, agricultural machines, forestry machines and construction machines. Examples of agricultural machines include such things as combines, tractors, sprayers, etc. Some examples of forestry machines include skidders, feller bunchers, knuckle boom loaders, swing machines, etc. Some examples of construction machines include dump trucks, loaders, excavators, among other things.

Each of these different types of machines are propelled by a propulsion system (such as an engine) that drives ground-engaging elements (such as rubber tires or tracks) through a transmission. These types of vehicles or machines often operate in environments which render them relatively unstable. For instance, when a loader is operating on a side hill, with a heavy load in a raised bucket, the stability of the loader can be compromised. This is just one example.

There are also some tire sensors available that provide information, in addition to tire pressure. For instance, some tire sensors are in-rubber sensors that sense, and generate an output indicative of, rubber temperature, the size of the contact patch of the rubber with the surface over which it is traveling, acceleration vectors, velocity vectors, tire deflection, and load.

The discussion above is merely provided for general background information and is not intended to be used as an aid in determining the scope of the claimed subject matter.

SUMMARY

A stability control system identifies an actionable condition, such as instability, in an off-road mobile machine, based upon an in-rubber sensor. A remedial action is identified, and a control signal is generated to control the mobile machine to take the remedial action.

This Summary is provided to introduce a selection of concepts in a simplified form that are further described below in the Detailed Description. This Summary is not intended to identify key features or essential features of the claimed subject matter, nor is it intended to be used as an aid in determining the scope of the claimed subject matter. The claimed subject matter is not limited to implementations that solve any or all disadvantages noted in the background.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 is a pictorial illustration of one example of an off-road mobile machine.

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FIG. 2 is a block diagram showing parts of the mobile machine illustrated in FIG. 1, in more detail.

FIG. 3 is a block diagram showing one example of a sensor signal processing system in more detail.

FIG. 4 is a block diagram showing one example of a stability control system in more detail.

FIG. 5 is a block diagram showing one example of a tire management system in more detail.

FIG. 6 is a flow diagram illustrating one example of the operation of the mobile machine in generating control signals based upon a tire sensor signal.

FIGS. 7 and 8 are additional examples of other mobile machines.

FIG. 9 is a block diagram showing one example of the mobile machine illustrated in FIG. 2, deployed in a cloud computing architecture.

FIGS. 10-12 show block diagrams of mobile devices that can be used in the architectures shown in the previous figures.

FIG. 13 is a block diagram of one example of a computing environment that can be used in the architectures shown in the previous figures.

DETAILED DESCRIPTION

FIG. 1 is a pictorial illustration of one example of a mobile work machine 100. In the example illustrated in FIG. 1, mobile work machine 100 is a loader that has a frame 102 that supports an operator compartment 104. Frame 102 also illustratively supports an engine compartment 106 that houses an engine that is used to drive a transmission which, in turn, drives ground-engaging elements 108 which, in the example shown in FIG. 1, are tires. It will be noted, however, that ground-engaging elements 108 can be other elements, such as tracks, etc.

Mobile work machine 100 also includes an implement (e.g., a bucket) 110 that is pivotably supported to boom 112 at connection 114. Boom 112 is pivotably supported to the frame 102 through a support member 116, at pivot axis 118. Pivotal movement of bucket 110 relative to boom 112 is illustratively driven by actuator 120. Actuator 120 can be any of a wide variety of actuators, such as a hydraulic cylinder or other actuator. Pivotal movement of boom 112 relative to support member 116 is illustratively driven by actuator 122 which can also be a hydraulic cylinder or other actuator.

Operator component 104 illustratively includes operator interface mechanisms that allow an operator to control and manipulate machine 100. The operator interface mechanisms in operator compartment 104 can be any of a wide variety of different types of mechanisms. For instance, they can include input mechanisms such as a steering wheel, levers, joysticks, buttons, pedals, switches, etc. In addition, operator compartment 104 may include an operator interface display device, such as a monitor, or mobile device that is supported within operator compartment 104. In that case, the operator interface mechanisms can also include user actuable elements displayed on the display device, such as icons, links, buttons, etc. The operator interface mechanisms can include a microphone where speech recognition is provided on machine 100. They can also include audio interface mechanisms (such as speakers), a haptic interface mechanism or a wide variety of other operator interface mechanisms. The operator interface mechanisms can include other output mechanisms as well, such as dials, gauges, meter outputs, lights, audible or visual alerts or haptic outputs, etc.

In the example shown in FIG. 1, each of the tires **108** illustratively include one or more in-rubber sensors systems **124** that are disposed within the rubber of the corresponding tire **108** and sense different variables and generate outputs based upon the sensed variables. As will be described in greater detail below, sensor systems **124** can output values indicative of tire pressure, rubber temperature, the size of the patch of rubber of tire **108** that is in contact with the surface over which it is traveling, acceleration vectors, velocity vectors, deflection, load, etc.

Also, as is discussed in greater detail below, machine **100** can have a variety of other sensors. Those sensors can include, for instance, position sensors that sense the relative position of bucket **110** relative to boom **112**. They can also include sensors that sense the relative position of boom **112** relative to frame **102** or support member **116**. Those types of sensors can include rotational potentiometers, angle encoders, Hall Effect sensors, or other sensors that sense the relative position of the two parts. They can also include sensors on hydraulic actuators **120** and **122** that sense the extent to which the corresponding actuator is retracted or extended. This, in combination with the known geometry of the various pieces on machine **100**, can provide an indication of the relative positions of the two pieces that are connected to the corresponding actuator. In addition, machine **100** can have a geographic position sensor, such as a GPS receiver or other sensor. It can have wheel speed sensors that sense the speed of rotation of wheels **108**. It can have a ground speed sensor that senses the speed of travel of machine **100** over the ground. It can have a wide variety of different sensors that sense the performance and other characteristics of the engine or other parts of machine **100**.

It will be appreciated that, during operation, machine **100** may become unstable, and in danger of tipping. By way of example, assume that machine **100** is carrying a relatively heavy load in bucket **110**, and the bucket **110** is raised to a relatively high position, relative to frame **102**. Assume also that machine **100** is traveling over sloped terrain. In that case, the center of gravity of machine **100** may be located in a position that renders it unstable, and in danger of tipping. By way of example, a line connecting the contact patches for each of the tires **108** (the contact patches for each tire being the area of each tire **108** that is in contact with the surface over which it is traveling) may define a polygon. If the center of gravity of machine **100** is outside that polygon, then machine **100** may be in danger of tipping (or may be unstable). Thus, in one example, the sensor signals output by sensors **124** can be used in controlling machine **100**, automatically, to perform stability control to reduce the likelihood that it enters an unstable condition, or to move it out of an unstable condition.

FIG. 2 is a block diagram showing one example of machine **100**. Some of the items in FIG. 2 are similar to those shown in FIG. 1, and they are similarly, numbered. FIG. 2 shows that, in one example, operator **126** provides inputs through operator input mechanisms **128** in order to control and manipulate mobile work machine **100**. Some of the examples of operator interface mechanisms **128** are described above. FIG. 2 also shows that, in one example, mobile work machine **100** can communicate with other mobile work machines **130** or other remote systems **132** over network **134**. Network **134** can include a wide area network, a local area network, a near field communication network, a cellular communication network or other networks or combinations of networks. In addition, as is

described in greater detail below, mobile work machine **100** can communicate with other systems using store and forward techniques as well.

Remote systems **132** can include remote computing systems or cloud-based systems, vendor or maintenance computing systems, manager computing systems, or a wide variety of other computing systems. These and other architectures are contemplated herein.

Also, in addition to the ground-engaging elements **108** and in-rubber sensor systems **124**, FIG. 2 shows that mobile work machine **100** can include vehicle sensors **136**, implement sensors **138**, and a wide variety of other sensors **140**. Some examples of those sensors were discussed above.

Machine **100** also includes one or more processors **142**, a data store **144**, sensor signal processing system **146**, control system **148**, controllable subsystems **150**, communication system **152**, and it can include a wide variety of other items **154**. Sensor signal processing system **146**, itself, illustratively includes conditioning logic **156**, control criteria extraction system **158**, and it can include other items **160**. Control system **148** illustratively includes load management system **162**, stability control system **164**, tire management system **166**, and it can include other control system functionality **168**. Controllable subsystems **150** illustratively include steering subsystem **170**, propulsion subsystem **172** (which, itself, can include engine **174**, transmission **176**, and other items **178**), actuators **180** and movable elements (or implements) **182**. Controllable subsystems **150** can include other items **184** as well. Before describing the overall operation of machine **100** in more detail, a brief description of some of the items in mobile work machine **100**, and their operation, will first be provided.

The ground-engaging elements **108** and in-rubber sensing systems **124** were briefly described above, as were some vehicle sensors **136**, implement sensors **138**, other sensors **140**, and operator interface mechanisms **128**.

Sensor signal processing system **146** illustratively receives the various sensor signals and can perform some processing on them. For instance, condition logic **156** can condition the sensor signals. The conditioning operations can include filtering, amplifying, linearizing, normalizing, among other things. Control criteria extraction system **158** then extracts various control criteria from the sensor signals. For instance, it can extract information such as the center of gravity of mobile work machine **100**, from the signals generated by in-rubber sensor systems **124**. It can extract information indicative of the number of rotations that each of the tires containing a sensor system **124** have performed. It can extract information indicative of the wear level of the ground-engaging elements **108**. It can extract information indicative of the traction that each of the tires has, the size of the contact patch (the part of each tire **108** that is in contact with the surface over which it is traveling), the condition of the pathway over which the tires are traveling, among other things.

The control criteria can be provided to control system **148** which generates control signals to control various controllable subsystems **150** based upon the control criteria. For instance, load management system **162** can generate control signals to control various actuators **180** that move the movable elements (e.g., boom **112** and bucket **110**) on mobile work machine **100**, based upon the current load. Stability control system **164** can generate control signals to avoid entering an unstable condition, or to control various portions of machine **100** so that it exits an unstable condition. By way of example, assume that the control criteria extraction system **158** extracts a center of gravity location

based upon the information from the various in-rubber sensor systems 124. If the center of gravity indicates that machine 100 is in an unstable condition, then stability control system 164 can generate control signals to control actuators 180 to lower bucket 110 or to control propulsion system 170 to reduce the speed of machine 100, or to control steering system 170 to limit the steering angle of machine 100, or to control a wide variety of the other controllable subsystems 150 to inhibit machine 100 from entering an unstable condition, or to address an unstable condition once it has been detected.

Tire management system 166 can generate control signals to control communication system 152 or operator interface mechanisms 128, or both, to provide information indicative of the wear on the various tires (or other ground-engaging elements) 108. It can also generate control signals to control propulsion subsystem 170, for example, to limit the travel speed of machine 100, where the tires have significant wear on them.

As briefly mentioned above, the steering subsystem 170 illustratively controls the steering of mobile work machine 100. It can be controlled based on inputs through operator interface mechanisms 128 (such as a steering wheel, a joystick, etc.).

Propulsion subsystem 170 illustratively includes engine 174 and transmission 176. These items can be controlled by operator inputs 126 through operator interface mechanisms 128 and control system 148.

Actuators 180 (which can be actuators 120 and 122) drive movement of the movable elements 182 on machine 100. The movable elements 182 can be boom 112, bucket 110, or a wide variety of other movable elements that are driven by actuators 180. The actuators 180 can also be controlled by operator inputs through operator interface mechanism 128, by control system 148, or in other ways.

Communication system 152 can be used to facilitate communication among various items on mobile work machine 100 (such as communication over a controller area network-CAN-bus) and also to facilitate communication between items on mobile work machine 100 and remote systems 132 or other mobile work machines 130 over network 134. Therefore, depending on the type of network 134 that is being used, communication system 152 may be any type of communication system that can be used to communicate over that type of network.

FIG. 3 is a block diagram showing one example of sensor signal processing system 146, in more detail. In the example illustrated, system 146 receives the sensor signals from in-rubber sensor systems 124. Those signals can provide values indicative of tire pressure 190, rubber temperature 192, contact patch size 194, acceleration vectors 196, velocity vectors 198, tire deflection 200, and tire load 202. As described above, the signals can be provided to conditioning logic 156 for signal conditioning, in order to obtain conditioned signals 204. The conditioned signals 204 are provided to system 158 for the extraction of various criteria that will be used by the items in control system 148 to control the controllable subsystems 150. Center of gravity identification logic 206 illustratively identifies the center of gravity of machine 100 based upon one or more of the signals. By way of example, using the load 202 on each of the tires, as well as knowing the configuration and/or dimension characteristics of machine 100, and further knowing the orientation of machine 100, logic 206 can identify the center of gravity of machine 100. It can identify a location of the center of gravity relative to the frame 102 of machine 100, relative to

a polygon bounded by a line joining the contact patches of tire various tires 106, or relative to machine 100 in other ways.

Contact patch change detection logic 208 illustratively identifies changes in the size of the contact patches for each of the tires 108. In an example where the contact patch size 194 is provided directly by the in-rubber sensor system 124, the contact patch sizes can be compared to one another over time to determine whether the contact patch size, for the same tire, for a given tire is increasing in size, decreasing in size, fluctuating, or remaining the same. In another example, logic 208 can calculate the contact patch size, itself, and then detect changes. By way of example, the velocity vectors 198 may indicate a rotational movement when the portion of the rubber that contains the sensor system 124 is not contacting the ground. However, once that portion of the rubber contacts the ground, the velocity vector will be generally linear, across the entire length of the contact patch. By knowing the width of the tires, the area of the contact patch can be calculated. Also, even if the width of the tires is not known, the length of the contact patch can be calculated by knowing the velocity of each of the tires and time during which the velocity vector is linear as opposed to rotational.

Traction detection logic 210 illustratively detects a characteristic of the traction of each of the tires 108. For example, it can use the velocity vectors 198 or acceleration vectors 196 to determine whether the tires are slipping. This may be indicative of the quality of traction that each of the tires currently has relative to the ground over which it is traveling.

Rotation detector logic 212 illustratively identifies the number of rotations of each of the tires. This can be identified from the acceleration or velocity vectors 196 or 198, respectively, and how they change as the rubber that contains sensor 124 engages the ground. It can be identified in other ways as well.

Wear identification logic 214 illustratively generates a value indicative of tire wear. For example, it can use an algorithm that takes into account the load 202 on each tire, the tire pressure 190 and rubber temperature 192 as well as tire deflection 200, and the number of rotations that a tire has undergone. Any or all of these values, and/or other values, can be used in an algorithm to estimate tire wear.

Pathway location identifier logic 216 illustratively generates an output indicative of a location of the pathway over which the corresponding tire 108 has traveled. By knowing the location of machine 100 (such as by using a GPS receiver), and by knowing the dimensional characteristics of machine 100, logic 216 illustratively knows the location of each of the tires 108 relative to the location provided by the GPS receiver. Thus, logic 216 can identify the path that was covered by each tire 108. This may be used, for instance, when machine 100 is attempting to travel over the same path in order to increase the compaction of the ground over which it is traveling. It may also be used in order to repeatedly travel over different paths, to avoid compaction. Similarly, it may be used to estimate the condition of the pathway, based upon the amount of traffic it has endured. These and other scenarios are contemplated herein.

Pathway condition identifier logic 218 illustratively generates a value indicative of the condition of the pathway, at various locations, over which each of the tires 108 has traveled. By way of example, if the acceleration or velocity vectors 196-198, or the load 202 or deflection values 200, or other signals, indicate that the corresponding tire is bouncing or otherwise losing contact with the ground, this may indicate that the condition of the pathway is degrading, and

it may need to be graded or that the surface should be otherwise treated. Similarly, the output from traction detection logic **210** may indicate that the tires are losing traction over the pathway at an increasing rate. This may also be used to indicate that the condition of the pathway is degrading. These and other scenarios are contemplated herein as well.

In addition, control criteria extraction system **158** can include other logic **220**. Other logic **220** can be used to extract other control criteria from the various sensor signals received by in-rubber sensor systems **124**.

FIG. **4** is one example of a more detailed block diagram of stability control system **164**. In the example illustrated in FIG. **4**, stability control system **164** includes actionable condition detection logic **222**, control signal generator logic **224**, and it can include a wide variety of other stability control functionality **226**. Actionable condition detection logic **222** illustratively includes instability detector **228**, remedial action identifier **230** and it can include other items **231**. Remedial action identifier **230** illustratively includes vehicle control action identifier **232** and implement control action identifier **234**. It can include other items **236** as well.

Instability detector **228** detects an instability condition which may be indicative of an unstable condition in machine **100** or that machine **100** is about to enter an unstable condition. Remedial action identifier **230** identifies a remedial action that can be taken to move machine **100** into a more stable condition, or to inhibit it from entering an unstable condition in the first place. Vehicle control action identifier **232** identifies a vehicle control action that can be taken to remedy the unstable condition. Implement control action identifier **234** identifies an implement control action that can be taken. Identifiers **232** and **234** can identify actions dynamically, using a dynamic model, taking the various sensor signals as inputs to the model. They can also use mappings or lookup tables to identify actions that will most quickly remedy various different instability conditions.

Similarly, instability detector **228** can detect an instability condition by identifying whether the center of gravity of machine **100** is within a threshold distance of a boundary which, if crossed, places machine **100** in an unstable condition. In addition, it can use the output from contact patch change detection logic **208** to determine whether a contact patch for one of the tires is shrinking to indicate that the tire may be about to lift off the ground. This may be an indication that machine **100** is about to tip over or become highly unstable. Detector **228** can use a wide variety of other indicators to identify whether machine **100** is entering an unstable state as well.

Control signal generator logic **224** generates control signals to implement the remedial action identified by remedial action identifier **230**. Therefore, logic **224** illustratively includes vehicle control logic **238**, implement control logic **240** and it can include other items **241**. Vehicle control logic **238** controls vehicle operations to perform the remedial action, while implement control logic **240** controls implement actions to perform the remedial action. It will of course be appreciated that both vehicle and implement actions may be taken in order to inhibit or eliminate an unstable condition as well.

Vehicle control logic **238** includes steering control logic **242**, engine control logic **244** (which, itself, includes torque controller **246**, speed controller **248**, and it can include other items **250**), transmission control logic **252**, braking control logic **254**, and it can include other items **256**. Steering control logic **242** may generate control signals that control the steering angle with which machine **100** is steered. In one example, the control signal can define a range of steering

angles that can be used to keep machine **100** in a stable condition. It can define limits on the steering angle in one direction or multiple directions, or it can generate control signals limiting the speed with which machine **100** is able to turn. For example, if machine **100** is carrying a load in bucket **110** in a relatively high position, and it is traveling relatively quickly, then steering control logic **242** may define limits on the sharpness with which the operator can turn machine **100**, so that it does not become unstable. These are examples only.

Engine control logic **244** can use torque controller **246** to control the torque applied by each of the tires. It can use speed controller **248** to control engine speed. For example, if machine **100** is in an unstable condition, or is about to enter an unstable condition, it may be that the acceleration of the machine should be limited. In that case, torque controller **246** limits the torque that can be applied to the tires. Similarly, it may be that the engine speed should be controlled. Engine speed controller **248** can limit or otherwise control the engine speed.

Transmission control logic **252** illustratively generates control signals to control transmission **176**. By way of example, it may limit the ability of the operator or another control system to shift gears in order to maintain machine **100** in a stable condition.

Braking control logic **254** can be used to generate braking control signals to control propulsion subsystem **170**. By way of example, if it is detected that machine **100** is in an unstable condition, or is about to enter an unstable condition, then it may be that braking control logic **254** limits the amount of braking that can be applied to avoid an unstable condition.

It should also be noted that the various items of logic in vehicle control logic **238** can be used in conjunction with one another. For instance, it may be that steering control logic **242** limits the sharpness of the steering angle with which machine **100** can be steered and, at the same time, braking control logic **254** limits the amount of braking that can be applied. This avoids a situation in which the operator attempts to steer mobile work machine very sharply, while also braking sharply. This is one example only.

Implement control logic **240** illustratively includes implement position control logic **258**, velocity control logic **260**, acceleration control logic **262**, load control logic **264**, and it can include other items **266**. Position control logic **258** illustratively generates control signals that control the positioning of a movable element (such as bucket **110** or boom **112**). By way of example, if the orientation of machine **100** is such that machine **100** would enter an unstable condition if bucket **110** were raised too high, then position control logic **258** can impose limits on the height to which the operator can control the corresponding actuator to raise the bucket. This is just one example.

It will also be noted that the dynamic movement (e.g., velocity and acceleration) of boom **112** and/or bucket **110** can be controlled as well. For example, velocity control logic **260** illustratively generates control signals to control the velocity with which actuators **180** can be actuated. By way of example, it may be that machine **100** would become unstable if bucket **110** were raised or lowered too quickly. In that case, velocity control logic **260** can generate control signals to limit the velocity with which the actuators **180** can be actuated.

Similarly, acceleration logic **262** can generate control signals to control the acceleration of the movable elements (such as bucket **110** and/or boom **112**) to avoid an unstable condition. For instance, if machine **100** would enter an

unstable condition if the operator raised the bucket with a relatively high rate of acceleration, then acceleration control logic 262 can generate control signals that limit the rate at which actuators 180 can be controlled to accelerate bucket 110. This is also just one example,

Load control logic 264 illustratively generates control signals that control actuators 180 to limit the load that can be carried by the implement (e.g., bucket 110). For instance, if machine 100 is oriented on a side hill, it may be that it would be unstable if bucket 110 were to engage a very heavy load and attempt to lift it. In such a scenario, load control logic 264 illustratively generates load control signals to limit the force that actuators 180 can exert on the movable elements 182. This, in effect, can limit the load that can be carried by movable elements 182 (e.g., by bucket 110). This is just one example.

FIG. 5 is a block diagram showing one example of tire management system 166 in more detail. In the example shown in FIG. 5, tire management system 166 illustratively includes tire lifetime estimation logic 268, load control logic 270, vehicle speed control logic 272, steering control logic 274, and it can include other items 276. Tire lifetime estimation logic 268 illustratively receives the tire wear identification information from wear identification logic 214 and generates an estimate or tire lifetime for each of the tires 108. Load control logic 270 can generate control signals to limit the amount of load that can be applied to the tires (e.g., the amount of load that can be lifted by bucket 110). Load control logic 270 can be similar to load control logic 264, or they can be different pieces of logic.

Vehicle speed control logic 272 illustratively generates control signals to control the speed of machine 100, given the estimated tire life. For instance, if the tires are highly worn and have a relatively short estimated tire life remaining, then it may be that vehicle speed control logic 272 generates a limit on the top speed with which operator 126 can drive machine 100. The value of the top machine speed limit may vary based upon the terrain over which machine 100 is traveling, based upon the temperature of the rubber, or based upon other items as well.

Steering control logic 274 generates control signals that control steering subsystem 170 based upon the estimated remaining tire life.

FIG. 6 is a flow diagram illustrating one example of the operation of sensor signal processing system 146 and control system 148 in generating control signals based upon the information provided by in-rubber sensor systems 124. It is first assumed that mobile work machine 100 includes the in-rubber sensor systems 124. Sensor signal processing system 146 then receives signals from the in-rubber sensor systems 124. This is indicated by block 280 in the flow diagram of FIG. 6. Conditioning logic 156 then performs any desired signal conditioning that may be performed on the various signals received from systems 124. Performing signal conditioning is indicated by block 282 in the flow diagram of FIG. 6.

Control criteria extraction system 158 then extracts the control criteria from the sensor signals received from in-rubber sensor systems 124. Extracting the control criteria is indicated by block 284 in the flow diagram of FIG. 6. By way of example, center of gravity identifying logic 206 can identify vehicle center of gravity as indicated by block 286. Contact patch change detection logic 208 illustratively detects changes in size of the contact patches for the various tires. This is indicated by block 288. Traction detection logic 210 detects a value indicative of the quality of traction that each tire has with the ground over which it is traveling. This

is indicated by block 290. Rotation detector logic 212 illustratively detects and accumulates the rotation counts for each of the tires. This is indicated by block 292. Wear identification logic 214 generates a value indicative of the wear on each of the tires. This is indicated by block 294. Pathway location identifier logic 216 identifies a pathway over which each tire has traveled. This is indicated by block 296. Pathway condition identifier logic 218 generates a value indicative of a condition of that pathway, at various locations along the pathway. This is indicated by block 298. It may, for instance, only identify areas of the pathway that need attention. Or it may identify the condition of the entire pathway. These and other scenarios are contemplated herein. Other control criteria can be extracted as well, and this is indicated by block 300.

Stability control system 164 then performs stability control operations. This is indicated by block 302. By way of example, instability detector 228 can identify an instability condition that indicates that machine 100 is in an unstable condition, or that it is about to become unstable. Identifying instability conditions is indicated by block 304. Remedial action identifier 230 then identifies a remedial action that can be taken to remedy the instability condition (the unstable condition in which machine 100 is currently in, or the condition that it is about to enter). Identifying remedial actions is indicated by block 306.

In one example, vehicle control action identifier 232 identifies remedial vehicle control actions and implement control action identifier 234 identifies remedial implement control actions. Control signal generator 224 then generates control signals based upon the identified remedial actions. Having vehicle control logic 238 generate vehicle control signals to implement the remedial action is indicated by block 308. In another example, implement control logic 240 can also, or instead, generate implement control signals to implement the remedial action. This is indicated by block 310. Performing stability operations can include other items as well, and this is indicated by block 312. Some other items can, for instance, be to control an operator interface mechanism to alert operator 126 that an unstable condition exists, or is about to exist. This can involve controlling user interface mechanisms 128 in order to display an alert, to sound an alert, or to otherwise identify the instability condition to operator 126. Of course, there can be a wide variety of other stability control operations as well.

Tire management system 166 then performs tire management control operations. This is indicated by block 314. By way of example, tire lifetime estimation logic 268 can estimate the remaining tire lifetime for each of the tires. This is indicated by block 316. Load control logic 270 can control the load that is engaged by machine 100. Controlling the load is indicated by block 318. Vehicle speed control logic 272 can control vehicle speed. This is indicated by block 320. Steering control logic 274 can perform steering control. This is indicated by block 322. By way of example, the steering control logic may control the steering subsystem so that machine 100 avoids pathways that are in rough condition, if the tire life is below a threshold value. It may inhibit operation of machine 100 on various surfaces, or in other places based upon the estimated tire lifetime. Other tire management control operations can be performed as well, and this is indicated by block 324.

Control system 148 can also control communication system 152 to generate any remote communications. This is indicated by block 326. For instance, control system 148 can control communication system 152 to generate tire maintenance or damage communications that indicate to a remote

vendor system 132 indicating that machine 100 needs its tires serviced, maintained or repaired. Generating tire maintenance/damage communications is indicated by block 328.

System 148 can also control communication system 152 to communicate a desired pathway to other mobile work machines 130. For instance, where it is desired to increase compaction of a pathway, then control system 148 may communicate the particular pathway taken by the tires of mobile work machine 100 to the other mobile work machines 130 so they can follow the same pathway, and thus increase compaction of the surface. Similarly, where compaction is to be avoided (such as with agricultural machines) then the pathway taken by machine 100 can be communicated to other mobile work machines 130 so that they can avoid using that exact same pathway. Controlling the pathway of other remote machines is indicated by block 330.

Control system 148 can also control communication system 152 to send pathway maintenance communications to other remote systems 132 or other work machines 130 that are tasked with maintaining a pathway. By way of example, if pathway condition identifier logic 218 provides information indicative of various locations of the pathway that have a condition that is degrading, and needs maintenance, then control system 148 can provide this information to communication system 152 and control communication system 152 to send the pathway maintenance communications to the other remote systems 132 or other mobile work machines 130. Sending pathway maintenance communications is indicated by block 332. The communication system 152 can be controlled to send other communications as well, and this is indicated by block 334.

Control system 148 can also perform any other desired control operations based upon the information from in-rubber sensor systems 124. This is indicated by block 336. By way of example, it can use load management system 162 to control the load carried by machine 100, based upon the wear on the particular tires, based upon the center of gravity of the machine at a given time, based upon the remaining tire lifetime, based upon the tire pressure, tire temperature, or the number of revolutions that the tires have undergone. It can control the load based upon the condition of the pathway over which machine 100 is traveling or other characteristics of the surface over which machine 100 is traveling. Control system 148 can also control the propulsion subsystem 170 and other actuators 180 to perform traction control. It can control the amount of torque and acceleration applied to each of the tires through the transmission 176 and by controlling engine 174. It can perform traction control to eliminate slippage in a wide variety of different ways. Control system 148 can also perform a wide variety of other control operations based on the information received from in-tire sensor systems 124. All of these configurations are contemplated herein.

FIGS. 7 and 8 are similar to FIG. 1, except that they show two different work machines. FIG. 7 shows that the mobile work machine can be a dump truck 340. Dump truck 340 illustratively has a dump box 342, that is controlled by actuators 344. It has an operator compartment 346 and an engine compartment 348. It also has a number of tires 350. Each of the tires 350 illustratively include an in-rubber sensor system 124. Thus, the same types of information described above with respect to machine 100 can be generated for machine 340 as well.

FIG. 8 is similar to FIGS. 1 and 7 above, except that the mobile work machine comprises an excavator 352 or any other machine in which the ground-engaging elements are rubber tracks 370. In the example shown in FIG. 8, exca-

vator 352 has an operator's compartment 356, movable elements 358 and 360 as well as bucket 362. The movement of elements 358 and 360 and bucket 362 are controlled by actuators 364, 366 and 368, respectively. Excavator 352 also has an engine with a transmission that drives rotation of tracks 370. Each of the tracks 370 illustratively has an in-rubber sensor system 124 that provides the same type of information discussed above. Thus, the type of information that can be used from sensor 124 includes the track pressure, the rubber temperature of track 370, the acceleration and velocity vectors detected in track 370, any type of track deflection, the load on track 370, the size of the contact patch (or the length of the contact patch) among a wide variety of other information. This can be used by control criteria extraction system 158 to extract a wide variety of different control criteria, such as those described above with respect to FIG. 3, or other criteria, that can be used to control excavator 352.

The present discussion has mentioned processors and servers. In one embodiment, the processors and servers include computer processors with associated memory and timing circuitry, not separately shown. They are functional parts of the systems or devices to which they belong and are activated by, and facilitate the functionality of the other components or items in those systems.

It will be noted that the above discussion has described a variety of different systems, components and/or logic. It will be appreciated that such systems, components and/or logic can be comprised of hardware items (such as processors and associated memory, or other processing components, some of which are described below) that perform the functions associated with those systems, components and/or logic. In addition, the systems, components and/or logic can be comprised of software that is loaded into a memory and is subsequently executed by a processor or server, or other computing component, as described below. The systems, components and/or logic can also be comprised of different combinations of hardware, software, firmware, etc., some examples of which are described below. These are only some examples of different structures that can be used to form the systems, components and/or logic described above. Other structures can be used as well.

Also, a number of user interface displays have been discussed. They can take a wide variety of different forms and can have a wide variety of different user actuatable input mechanisms disposed thereon. For instance, the user actuatable input mechanisms can be text boxes, check boxes, icons, links, drop-down menus, search boxes, etc. They can also be actuated in a wide variety of different ways. For instance, they can be actuated using a point and click device (such as a track ball or mouse). They can be actuated using hardware buttons, switches, a joystick or keyboard, thumb switches or thumb pads, etc. They can also be actuated using a virtual keyboard or other virtual actuators. In addition, where the screen on which they are displayed is a touch sensitive screen, they can be actuated using touch gestures. Also, where the device that displays them has speech recognition components, they can be actuated using speech commands.

A number of data stores have also been discussed. It will be noted they can each be broken into multiple data stores. All can be local to the systems accessing them, all can be remote, or some can be local while others are remote. All of these configurations are contemplated herein.

Also, the figures show a number of blocks with functionality ascribed to each block. It will be noted that fewer blocks can be used so the functionality is performed by

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fewer components. Also, more blocks can be used with the functionality distributed among more components.

FIG. 9 is a block diagram of machine 100, shown in FIG. 2, except that it communicates with elements in a remote server architecture 500. In an example, remote server architecture 500 can provide computation, software, data access, and storage services that do not require end-user knowledge of the physical location or configuration of the system that delivers the services. In various examples, remote servers can deliver the services over a wide area network, such as the internet, using appropriate protocols. For instance, remote servers can deliver applications over a wide area network and they can be accessed through a web browser or any other computing component. Software or components shown in FIG. 1 as well as the corresponding data, can be stored on servers at a remote location. The computing resources in a remote server environment can be consolidated at a remote data center location or they can be dispersed. Remote server infrastructures can deliver services through shared data centers, even though they appear as a single point of access for the user. Thus, the components and functions described herein can be provided from a remote server at a remote location using a remote server architecture. Alternatively, they can be provided from a conventional server, or they can be installed on client devices directly, or in other ways.

In the example shown in FIG. 9, some items are similar to those shown in FIG. 2 and they are similarly numbered. FIG. 9 specifically shows that remote system(s) 132 can be located at a remote server location 502. Therefore, machine 100 accesses those systems through remote server location 502.

FIG. 9 also depicts another example of a remote server architecture. FIG. 9 shows that it is also contemplated that some elements of FIG. 2 are disposed at remote server location 502 while others are not. By way of example, data store 144 or other components 506 can be disposed at a location separate from location 502, and accessed through the remote server at location 502. Regardless of where they are located, they can be accessed directly by machine 100, through a network (either a wide area network or a local area network), they can be hosted at a remote site by a service, or they can be provided as a service, or accessed by a connection service that resides in a remote location. Also, the data can be stored in substantially any location and intermittently accessed by, or forwarded to, interested parties. For instance, physical carriers can be used instead of, or in addition to, electromagnetic wave carriers. In such an example, where cell coverage is poor or nonexistent, another mobile machine (such as a fuel truck) can have an automated information collection system. As the machine 100 comes close to the fuel truck for fueling, the system automatically collects the information from the machine 100 using any type of ad-hoc wireless connection. The collected information can then be forwarded to the main network as the fuel truck reaches a location where there is cellular coverage (or other wireless coverage). For instance, the fuel truck may enter a covered location when traveling to fuel other machines or when at a main fuel storage location. All of these architectures are contemplated herein. Further, the information can be stored on the machine 100 until the machine 100 enters a covered location. The machine 100, itself, can then send the information to the main network.

It will also be noted that the elements of FIG. 2, or portions of them, can be disposed on a wide variety of different devices. Some of those devices include servers, desktop computers, laptop computers, tablet computers, or

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other mobile devices, such as palm top computers, cell phones, smart phones, multimedia players, personal digital assistants, etc.

FIG. 10 is a simplified block diagram of one illustrative example of a handheld or mobile computing device that can be used as a user's or client's hand held device 16, in which the present system (or parts of it) can be deployed. For instance, a mobile device can be deployed in the operator compartment of machine 100 for use in generating, processing, or displaying the control signals. FIGS. 11-12 are examples of handheld or mobile devices.

FIG. 10 provides a general block diagram of the components of a client device 16 that can run some components shown in FIG. 1, that interacts with them, or both. In the device 16, a communications link 13 is provided that allows the handheld device to communicate with other computing devices and under some examples provides a channel for receiving information automatically, such as by scanning. Examples of communications link 13 include allowing communication through one or more communication protocols, such as wireless services used to provide cellular access to a network, as well as protocols that provide local wireless connections to networks.

In other examples, applications can be received on a removable Secure Digital (SD) card that is connected to an interface 15. Interface 15 and communication links 13 communicate with a processor 17 (which can also embody processors from previous FIGS.) along a bus 19 that is also connected to memory 21 and input/output (I/O) components 23, as well as clock 25 and location system 27.

I/O components 23, in one example, are provided to facilitate input and output operations. I/O components 23 for various examples of the device 16 can include input components such as buttons, touch sensors, optical sensors, microphones, touch screens, proximity sensors, accelerometers, orientation sensors and output components such as a display device, a speaker, and or a printer port. Other I/O components 23 can be used as well.

Clock 25 illustratively comprises a real time clock component that outputs a time and date. It can also, illustratively, provide timing functions for processor 17.

Location system 27 illustratively includes a component that outputs a current geographical location of device 16. This can include, for instance, a global positioning system (GPS) receiver, a LORAN system, a dead reckoning system, a cellular triangulation system, or other positioning system. It can also include, for example, mapping software or navigation software that generates desired maps, navigation routes and other geographic functions.

Memory 21 stores operating system 29, network settings 31, applications 33, application configuration settings 35, data store 37, communication drivers 39, and communication configuration settings 41. Memory 21 can include all types of tangible volatile and non-volatile computer-readable memory devices. It can also include computer storage media (described below). Memory 21 stores computer readable instructions that, when executed by processor 17, cause the processor to perform computer-implemented steps or functions according to the instructions. Processor 17 can be activated by other components to facilitate their functionality as well.

FIG. 11 shows one example in which device 16 is a tablet computer 600. In FIG. 11, computer 600 is shown with user interface display screen 602. Screen 602 can be a touch screen or a pen-enabled interface that receives inputs from a pen or stylus. It can also use an on-screen virtual keyboard. Of course, it might also be attached to a keyboard or other

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user input device through a suitable attachment mechanism, such as a wireless link or USB port, for instance. Computer 600 can also illustratively receive voice inputs as well.

FIG. 12 shows that the device can be a smart phone 71. Smart phone 71 has a touch sensitive display 73 that displays icons or tiles or other user input mechanisms 75. Mechanisms 75 can be used by a user to run applications, make calls, perform data transfer operations, etc. In general, smart phone 71 is built on a mobile operating system and offers more advanced computing capability and connectivity than a feature phone.

Note that other forms of the devices 16 are possible.

FIG. 13 is one example of a computing environment in which elements of FIG. 2, or parts of it, (for example) can be deployed. With reference to FIG. 13, an example system for implementing some embodiments includes a general-purpose computing device in the form of a computer 810. Components of computer 810 may include, but are not limited to, a processing unit 820 (which can comprise processors from previous FIGS.), a system memory 830, and a system bus 821 that couples various system components including the system memory to the processing unit 820. The system bus 821 may be any of several types of bus structures including a memory bus or memory controller, a peripheral bus, and a local bus using any of a variety of bus architectures. Memory and programs described with respect to FIG. 1 can be deployed in corresponding portions of FIG. 13.

Computer 810 typically includes a variety of computer readable media. Computer readable media can be any available media that can be accessed by computer 810 and includes both volatile and nonvolatile media, removable and non-removable media. By way of example, and not limitation, computer readable media may comprise computer storage media and communication media. Computer storage media is different from, and does not include, a modulated data signal or carrier wave. It includes hardware storage media including both volatile and nonvolatile, removable and non-removable media implemented in any method or technology for storage of information such as computer readable instructions, data structures, program modules or other data. Computer storage media includes, but is not limited to, RAM, ROM, EEPROM, flash memory or other memory technology, CD-ROM, digital versatile disks (DVD) or other optical disk storage, magnetic cassettes, magnetic tape, magnetic disk storage or other magnetic storage devices, or any other medium which can be used to store the desired information and which can be accessed by computer 810. Communication media may embody computer readable instructions, data structures, program modules or other data in a transport mechanism and includes any information delivery media. The term “modulated data signal” means a signal that has one or more of its characteristics set or changed in such a manner as to encode information in the signal.

The system memory 830 includes computer storage media in the form of volatile and/or nonvolatile memory such as read only memory (ROM) 831 and random access memory (RAM) 832. A basic input/output system 833 (BIOS), containing the basic routines that help to transfer information between elements within computer 810, such as during start-up, is typically stored in ROM 831. RAM 832 typically contains data and/or program modules that are immediately accessible to and/or presently being operated on by processing unit 820. By way of example, and not limitation, FIG. 13 illustrates operating system 834, application programs 835, other program modules 836, and program data 837.

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The computer 810 may also include other removable/non-removable volatile/nonvolatile computer storage media. By way of example only, FIG. 13 illustrates a hard disk drive 841 that reads from or writes to non-removable, nonvolatile magnetic media, an optical disk drive 855, and nonvolatile optical disk 856. The hard disk drive 841 is typically connected to the system bus 821 through a non-removable memory interface such as interface 840, and optical disk drive 855 are typically connected to the system bus 821 by a removable memory interface, such as interface 850.

Alternatively, or in addition, the functionality described herein can be performed, at least in part, by one or more hardware logic components. For example, and without limitation, illustrative types of hardware logic components that can be used include Field-programmable Gate Arrays (FPGAs), Application-specific Integrated Circuits (e.g., ASICs), Application-specific Standard Products (e.g., ASSPs), System-on-a-chip systems (SOCs), Complex Programmable Logic Devices (CPLDs), etc.

The drives and their associated computer storage media discussed above and illustrated in FIG. 13, provide storage of computer readable instructions, data structures, program modules and other data for the computer 810. In FIG. 13, for example, hard disk drive 841 is illustrated as storing operating system 844, application programs 845, other program modules 846, and program data 847. Note that these components can either be the same as or different from operating system 834, application programs 835, other program modules 836, and program data 837.

A user may enter commands and information into the computer 810 through input devices such as a keyboard 862, a microphone 863, and a pointing device 861, such as a mouse, trackball or touch pad. Other input devices (not shown) may include a joystick, game pad, satellite dish, scanner, or the like. These and other input devices are often connected to the processing unit 820 through a user input interface 860 that is coupled to the system bus, but may be connected by other interface and bus structures. A visual display 891 or other type of display device is also connected to the system bus 821 via an interface, such as a video interface 890. In addition to the monitor, computers may also include other peripheral output devices such as speakers 897 and printer 896, which may be connected through an output peripheral interface 895.

The computer 810 is operated in a networked environment using logical connections (such as a local area network—LAN, or wide area network WAN) to one or more remote computers, such as a remote computer 880.

When used in a LAN networking environment, the computer 810 is connected to the LAN 871 through a network interface or adapter 870. When used in a WAN networking environment, the computer 810 typically includes a modem 872 or other means for establishing communications over the WAN 873, such as the Internet. In a networked environment, program modules may be stored in a remote memory storage device. FIG. 13 illustrates, for example, that remote application programs 885 can reside on remote computer 880.

It should also be noted that the different examples described herein can be combined in different ways. That is, parts of one or more examples can be combined with parts of one or more other examples. All of this is contemplated herein.

Example 1 is a mobile work machine, comprising:
a set of controllable subsystems;
a set of ground engaging elements;

a propulsion system configured to drive movement of the ground engaging elements to propel the mobile work machine over a surface;

an in-rubber sensing system, in each of the ground engaging elements, configured to sense a set of variables indicative of characteristics of a contact patch of each corresponding ground engaging element and generate sensor signals, indicative of a contact patch value for each corresponding ground engaging element;

a control criteria extraction system configured to identify a change in the contact patch value for one or more of the corresponding ground engaging elements based on the set of sensor signals; and

a control system configured to generate a control signal to control at least one of the controllable subsystems based on the identified change in the contact patch value for the one or more corresponding ground engaging elements.

Example 2 is the mobile work machine of any or all previous examples, wherein the identified change in the contact patch value indicates that a size of the contact patch for the one or more corresponding ground engaging elements is decreasing, the mobile work machine further comprising:

an instability detector configured to identify an instability condition indicative of instability of the mobile work machine, based on the decreasing size of the contact patch for the one or more corresponding ground engaging elements, and wherein the control system generates the control signal to control at least one of the controllable subsystems based on the instability condition.

Example 3 is the mobile work machine of any or all previous examples, wherein the in-rubber sensing system, in each of the ground engaging elements, are further configured to:

sense a set of variables indicative of a temperature of each of the ground engaging elements and generate additional sensor signals indicative of a temperature value for each corresponding ground engaging element;

sense a set of variables indicative of an internal pressure of each of the ground engaging elements and generate additional sensor signals indicative of an internal pressure value for each corresponding ground engaging element;

sense a set of variables indicative of a load of each of the ground engaging elements and generate additional sensor signals indicative of a load value for each corresponding ground engaging element;

sense a set of variables indicative of a velocity vector of each of the ground engaging elements and generate additional sensor signals indicative of the velocity vector for each corresponding ground engaging element;

sense a set of variables indicative of an acceleration vector of each of the ground engaging elements and generate additional sensor signals indicative of the acceleration vector for each corresponding ground engaging element; and

sense a set of variables indicative of deflection of each of the ground engaging elements and generate additional sensor signals indicative of a deflection value for each corresponding ground engaging element.

Example 4 is the mobile work machine of any or all previous examples, wherein control criteria extraction system further comprises:

traction detection logic configured to generate an output indicative of a traction of each ground engaging element;

rotation identification logic configured to generate an output indicative of a number of rotations of each ground engaging element; and

wear identification logic configured to generate an output indicative of a wear of each ground engaging element.

Example 5 is the mobile work machine of any or all previous examples, wherein the control system is configured to generate additional control signals to control one or more of the controllable subsystems based on one or more of the outputs.

Example 6 is the mobile work machine of any or all previous examples wherein the control criteria extraction system further comprises:

center of gravity identifying logic configured to, based on the contact patch value for each corresponding ground engaging element, identify a location of a center of gravity of the mobile work machine relative to a polygon bounded by a line joining the contact patches of the ground engaging elements.

Example 7 is the mobile work machine of any or all previous examples further comprising:

an instability detector configured to identify an instability condition indicative of instability of the mobile work machine, based on the location of the center of gravity of the mobile work machine relative to the polygon bounded by the line joining the contact patches of the ground engaging elements.

Example 8 is the mobile work machine of any or all previous examples, wherein the control criteria extraction system further comprises:

pathway condition identifier logic configured to generate an output indicative of a condition of the pathway traveled by each ground engaging element.

Example 10 is the mobile work machine of any or all previous examples further comprising:

a location sensor configured to generate sensor signals indicative of locations of the mobile work machine as the mobile machine travels over the surface; and

pathway location identifier logic configured to identify a location of a pathway traveled by each ground engaging element, based on the contact patch value corresponding to each ground engaging element and the location of the mobile machine.

Example 11 is the mobile work machine of any or all previous examples wherein the control signal controls a route of the mobile work machine to align a prospective path of the ground engaging elements of the mobile work machine relative to the identified location of the pathway traveled by each ground engaging element, to control a compaction of the pathway traveled by each ground engaging element.

Example 12 is the mobile work machine of any or all previous examples further comprising:

a communication system;

wherein the control system is configured to control the communication system to send the control signal to another mobile work machine to control a route of the other mobile work machine to align a prospective path of ground engaging elements of the other mobile work machine relative to the identified location of the pathway traveled by each ground engaging element of the mobile work machine, to control a compaction of the pathway traveled by each ground engaging element of the mobile work machine.

Example 13 is a computer implemented method of controlling a mobile work machine, the method comprising:

sensing, with an in-rubber sensing system, a set of variables indicative of characteristics of a contact patch of each of a plurality of ground engaging elements that are configured to be driven by a propulsion subsystem of the mobile

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work machine to propel the mobile work machine in a direction of travel over a surface;

generating a set of sensor signals indicative of a contact patch value for each ground engaging element, of the plurality of ground engaging element, based on the set of variables;

identifying a change in the contact patch value for one or more of the ground engaging elements, based on the set of sensor signals; and

generating a control signal to control one or more controllable subsystems of the mobile work machine based on the change in the contact patch value for one or more of the ground engaging elements.

Example 14 is the method of any or all previous examples, wherein identifying a change in the contact patch value comprises identifying a decrease in a size of the contact patch of one or more of the ground engaging elements and wherein generating the control signal to control the one or more controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

detecting an instability condition indicative of instability of the mobile work machine, based on the decrease in size of the contact patch of one or more of the ground engaging elements;

identifying a remedial action based on the instability condition; and

generating the control signal to control one or more of the controllable subsystems to perform the remedial action.

Example 15 is the method of any or all previous examples, wherein one of the controllable subsystems comprises a steering subsystem that is actuatable to steer the mobile work machine through a range of steering angles and wherein generating the control signal to control one or more of the controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

generating a steering angle control signal to control the steering subsystem to limit a range of steering angles.

Example 16 is the method of any or all previous examples, wherein one of the controllable subsystems comprises an actuator configured to drive movement of a movable element attached to the mobile work machine and wherein generating the control signal to control one or more of the controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

generating a movable element control signal to control the actuator to control a position of the movable element.

Example 17 is the method of any or all previous examples, wherein the one of the controllable subsystems comprises the propulsion subsystem and wherein generating the control signal to control one or more of the controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

generating a propulsion control signal to control the propulsion subsystem to control a travel speed of the mobile work machine.

Example 18 is the method of any or all previous examples, wherein one of the controllable subsystems comprises an actuator configured to drive movement of a movable element attached to the mobile work machine and wherein generating the control signal to control one or more of the controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

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generating a load control signal to control the actuator to limit a load that can be carried by the movable element.

Example 19 is the method of any or all previous examples and further comprising:

identifying a size of the contact patch of each ground engaging element, based on the contact patch value for each corresponding ground engaging element;

identifying a location of a center of gravity of the mobile work machine relative to a polygon bounded by a line joining the contact patches of the ground engaging elements; and

generating an additional control signal to control one or more the controllable subsystems based on the identified location of the center of gravity of the mobile work machine relative to the polygon bounded by the line joining the contact patches of the ground engaging elements.

Example 20 is a mobile work machine, comprising:

a set of controllable subsystems;

a set of ground engaging elements;

a propulsion system configured to drive movement of the ground engaging elements to propel the mobile work machine over a surface;

an in-rubber sensing system, in each of the ground engaging elements, configured to sense a set of variables indicative of characteristics of a contact patch of each ground engaging element and generate a set of sensor signals indicative of a contact patch value for each corresponding ground engaging element based on the characteristic of the contact patch of each ground engaging element;

a control criteria extraction system configured to identify a change in the contact patch value of one or more of the ground engaging elements;

an instability detector configured to identify an instability condition indicative of instability of the mobile work machine based on the identified change in the contact patch value of one or more of the ground engaging elements; and

a control system configured to generate a control signal to control one or more controllable subsystems based on the instability condition.

Although the subject matter has been described in language specific to structural features and/or methodological acts, it is to be understood that the subject matter defined in the appended claims is not necessarily limited to the specific features or acts described above. Rather, the specific features and acts described above are disclosed as example forms of implementing the claims.

What is claimed is:

1. A mobile work machine, comprising:

a set of controllable subsystems;

a set of ground engaging elements;

a propulsion system configured to drive movement of the ground engaging elements to propel the mobile work machine over a surface;

an in-rubber sensing system, in each of the ground engaging elements, configured to sense a set of variables indicative of characteristics of a contact patch of each corresponding ground engaging element and generate sensor signals, indicative of a contact patch value for each corresponding ground engaging element;

one or more processors; and

a data store configured to store a set of computer executable instructions that, when executed by the one or more processors, configure the one or more processors to:

identify a change in the contact patch value for one or more of the corresponding ground engaging elements based on the set of sensor signals; and

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generate a control signal to control at least one of the controllable subsystems based on the identified change in the contact patch value for the one or more corresponding ground engaging elements.

2. The mobile work machine of claim 1, wherein the identified change in the contact patch value indicates that a size of the contact patch for the one or more corresponding ground engaging elements is decreasing, and wherein the computer executable instructions, when executed by the one or more processors, further configure the one or more processors to:

identify an instability condition indicative of instability of the mobile work machine, based on the decreasing size of the contact patch for the one or more corresponding ground engaging elements; and

generate the control signal to control at least one of the controllable subsystems based on the instability condition.

3. The mobile work machine of claim 1, wherein the in-rubber sensing system, in each of the ground engaging elements, are further configured to:

sense a set of variables indicative of a temperature of each of the ground engaging elements and generate additional sensor signals indicative of a temperature value for each corresponding ground engaging element;

sense a set of variables indicative of an internal pressure of each of the ground engaging elements and generate additional sensor signals indicative of an internal pressure value for each corresponding ground engaging element;

sense a set of variables indicative of a load of each of the ground engaging elements and generate additional sensor signals indicative of a load value for each corresponding ground engaging element;

sense a set of variables indicative of a velocity vector of each of the ground engaging elements and generate additional sensor signals indicative of the velocity vector for each corresponding ground engaging element;

sense a set of variables indicative of an acceleration vector of each of the ground engaging elements and generate additional sensor signals indicative of the acceleration vector for each corresponding ground engaging element; and

sense a set of variables indicative of deflection of each of the ground engaging elements and generate additional sensor signals indicative of a deflection value for each corresponding ground engaging element.

4. The mobile work machine of claim 1, wherein the computer executable instructions, when executed by the one or more processors, further configure the one or more processors to:

generate an output indicative of a traction of each ground engaging element;

generate an output indicative of a number of rotations of each ground engaging element; and

generate an output indicative of a wear of each ground engaging element.

5. The mobile work machine of claim 4, wherein the computer executable instructions, when executed by the one or more processors, further configure the one or more processors to:

generate additional control signals to control one or more of the controllable subsystems based on one or more of the outputs.

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6. The mobile work machine of claim 1, wherein the computer executable instructions, when executed by the one or more processors, further configure the one or more processors:

identify, based on the contact patch value for each corresponding ground engaging element, a location of a center of gravity of the mobile work machine relative to a polygon bounded by a line joining the contact patches of the ground engaging elements.

7. The mobile work machine of claim 6, wherein the computer executable instructions, when executed by the one or more processors, further configure the one or more processors to:

identify an instability condition indicative of instability of the mobile work machine, based on the location of the center of gravity of the mobile work machine relative to the polygon bounded by the line joining the contact patches of the ground engaging elements.

8. The mobile work machine of claim 1, wherein the computer executable instructions, when executed by the one or more processors, further configure the one more processors to:

generate an output indicative of a condition of the pathway traveled by each ground engaging element.

9. The mobile work machine of claim 1 further comprising:

a location sensor configured to generate sensor signals indicative of locations of the mobile work machine as the mobile machine travels over the surface; and

wherein the computer executable instructions, when executed by the one or more processors, further configure the one or more processors to:

identify a location of a pathway traveled by each ground engaging element, based on the contact patch value corresponding to each ground engaging element and the location of the mobile machine.

10. The mobile work machine of claim 9 wherein the control signal controls a route of the mobile work machine to align a prospective path of the ground engaging elements of the mobile work machine relative to the identified location of the pathway traveled by each ground engaging element, to control a compaction of the pathway traveled by each ground engaging element.

11. The mobile work machine of claim 9 further comprising:

a communication system;

wherein the computer executable instructions, when executed by the one or more processors, further configure the one or more processors to:

control the communication system to send the control signal to another mobile work machine to control a route of the other mobile work machine to align a prospective path of ground engaging elements of the other mobile work machine relative to the identified location of the pathway traveled by each ground engaging element of the mobile work machine, to control a compaction of the pathway traveled by each ground engaging element of the mobile work machine.

12. A computer implemented method of controlling a mobile work machine, the method comprising:

sensing, with an in-rubber sensing system, a set of -variables indicative of characteristics of a contact patch of each of a plurality of ground engaging elements that are configured to be driven by a propulsion subsystem of the mobile work machine to propel the mobile work machine in a direction of travel over a surface;

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generating a set of sensor signals indicative of a contact patch value for each ground engaging element, of the plurality of ground engaging element, based on the set of variables;

identifying a change in the contact patch value the one or more of the ground engaging elements, based on the set of sensor signals; and

generating a control signal to control one or more controllable subsystems of the mobile work machine based on the change in the contact patch value for one or more of the ground engaging elements.

13. The method of claim **12**, wherein identifying a change in the contact patch value comprises identifying a decrease in a size of the contact patch of one or more of the ground engaging elements and wherein generating the control signal to control the one or more controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

detecting an instability condition indicative of instability of the mobile work machine, based on the decrease in size of the contact patch of one or more of the ground engaging elements;

identifying a remedial action based on the instability condition; and

generating the control signal to control one or more of the controllable subsystems to perform the remedial action.

14. The method of claim **12**, wherein one of the controllable subsystems comprises a steering subsystem that is actuatable to steer the mobile work machine through a range of steering angles and wherein generating the control signal to control one or more of the controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

generating a steering angle control signal to control the steering subsystem to limit a range of steering angles.

15. The method of claim **12**, wherein one of the controllable subsystems comprises an actuator configured to drive movement of a movable element attached to the mobile work machine and wherein generating the control signal to control one or more of the controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

generating a movable element control signal to control the actuator to control a position of the movable element.

16. The method of claim **12**, wherein the one of the controllable subsystems comprises the propulsion subsystem and wherein generating the control signal to control one or more of the controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

generating a propulsion control signal to control the propulsion subsystem to control a travel speed of the mobile work machine.

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17. The method of claim **12**, wherein one of the controllable subsystems comprises an actuator configured to drive movement of a movable element attached to the mobile work machine and wherein generating the control signal to control one or more of the controllable subsystems based on the change in the contact patch value for one or more of the ground engaging elements comprises:

generating a load control signal to control the actuator to limit a load that can be carried by the movable element.

18. The method of claim **12** and further comprising:

identifying a size of the contact patch of each ground engaging element, based on the contact patch value for each corresponding ground engaging element;

identifying a location of a center of gravity of the mobile work machine relative to a polygon bounded by a line joining the contact patches of the ground engaging elements; and

generating an additional control signal to control one or more the controllable subsystems based on the identified location of the center of gravity of the mobile work machine relative to the polygon bounded by the line joining the contact patches of the ground engaging elements.

19. A mobile work machine, comprising:

a set of controllable subsystems;

a set of ground engaging elements;

a propulsion system configured to drive movement of the ground engaging elements to propel the mobile work machine over a surface;

an in-rubber sensing system, in each of the ground engaging elements, configured to sense a set of variables indicative of characteristics of a contact patch of each ground engaging element and generate a set of sensor signals indicative of a contact patch value for each corresponding ground engaging element based on the characteristic of the contact patch of each ground engaging element;

one or more processors; and

a data store configured to store computer executable instructions that, when executed by the one or more processors, configure the one or more processors to:

identify a change in the contact patch value of one or more of the ground engaging elements;

identify an instability condition indicative of instability of the mobile work machine based on the identified change in the contact patch value of one or more of the ground engaging elements; and

generate a control signal to control one or more controllable subsystems based on the instability condition.

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